

The Decade of the Geopotential – techniques to observe the gravity field from space

Matthias Weigelt

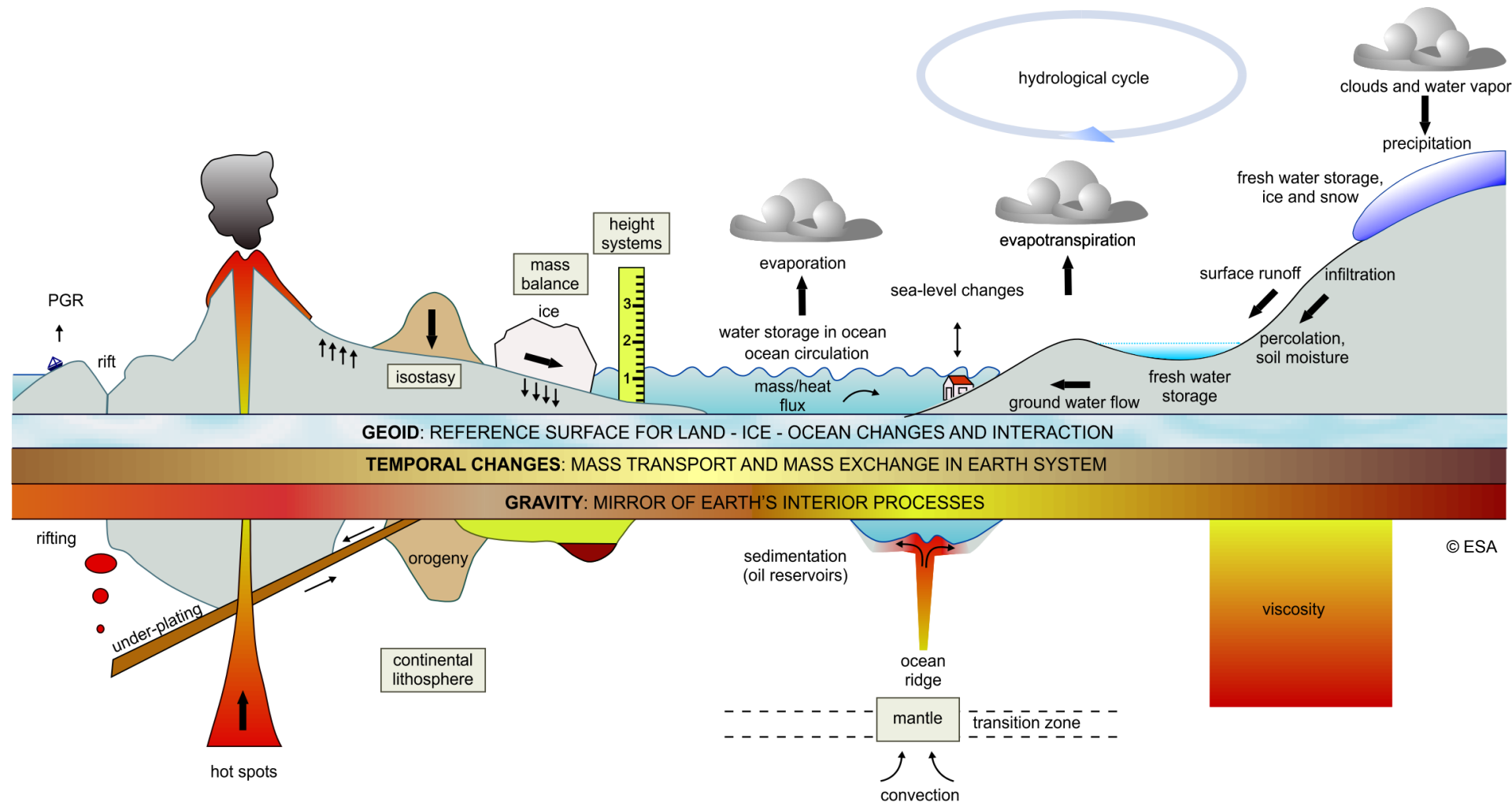
Tonie van Dam

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Geophysical implications of the gravity field



Gravity field modelling

$$V = \frac{GM}{R} \sum_{l=0}^{\infty} \left(\frac{R}{r} \right)^{l+1} \sum_{m=0}^l \bar{P}_{lm} (\sin \phi) (\bar{C}_{lm} \cos m\lambda + \bar{S}_{lm} \sin m\lambda)$$

with	GM	gravitational constant times mass of the Earth
	R	radius of the Earth
	r, ϕ, λ	spherical coordinates of the calculation point
	\bar{P}_{lm}	Legendre function
	l, m	degree, order
	$\bar{C}_{lm}, \bar{S}_{lm}$	(unknown) spherical harmonic coefficients

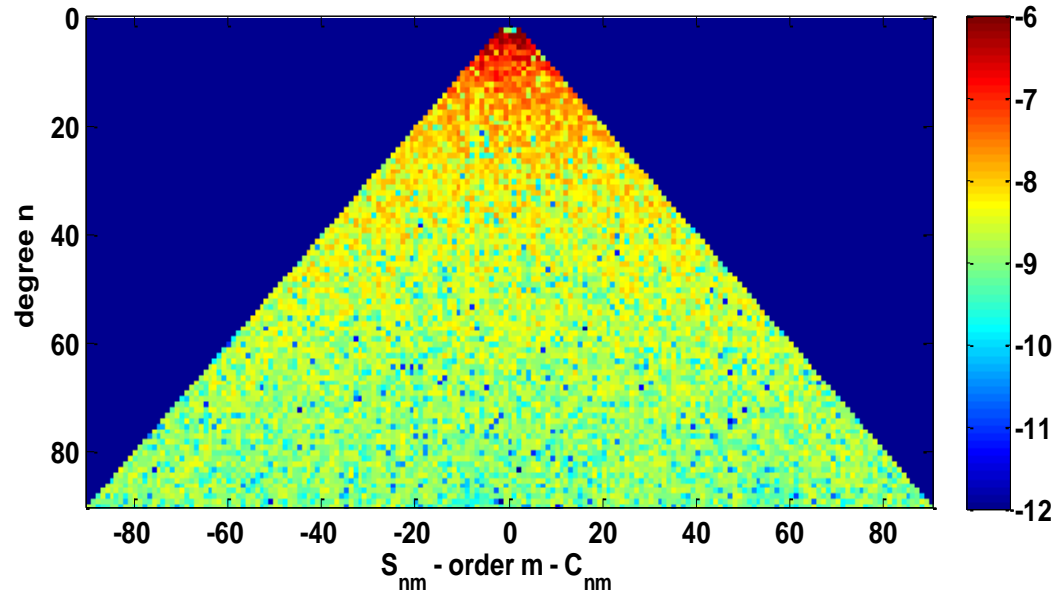
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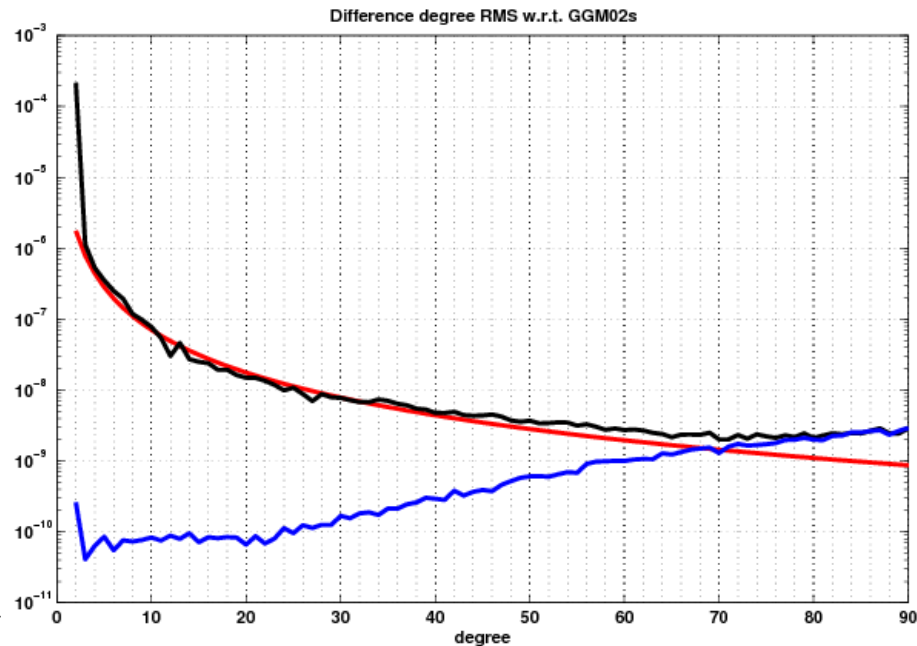
Spectral representation

Spherical
harmonic
representation



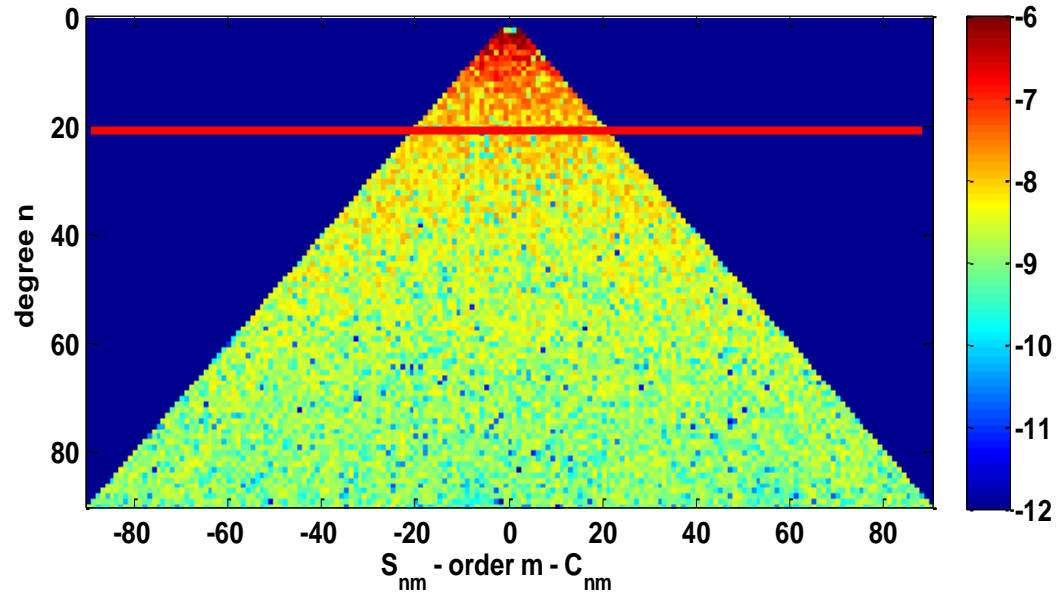
degree-RMS

$$c_n = \sqrt{\frac{1}{n} \sum_{m=0}^n \bar{C}_{nm}^2 + \bar{S}_{nm}^2}$$



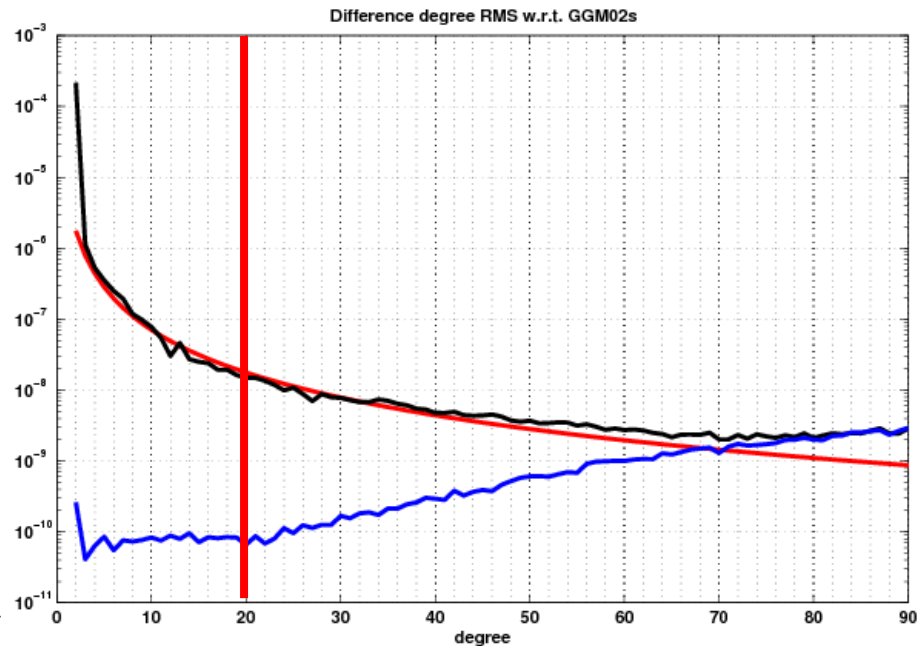
Spectral representation

Spherical
harmonic
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degree-RMS

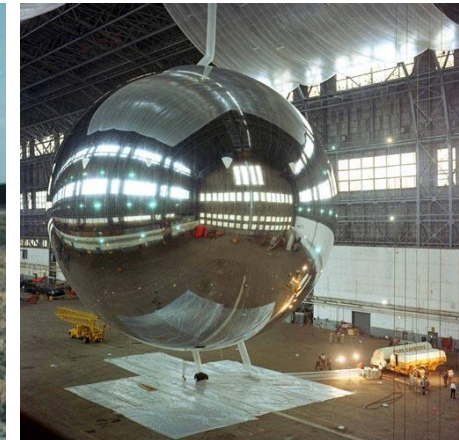
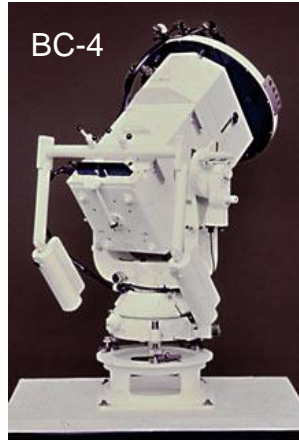
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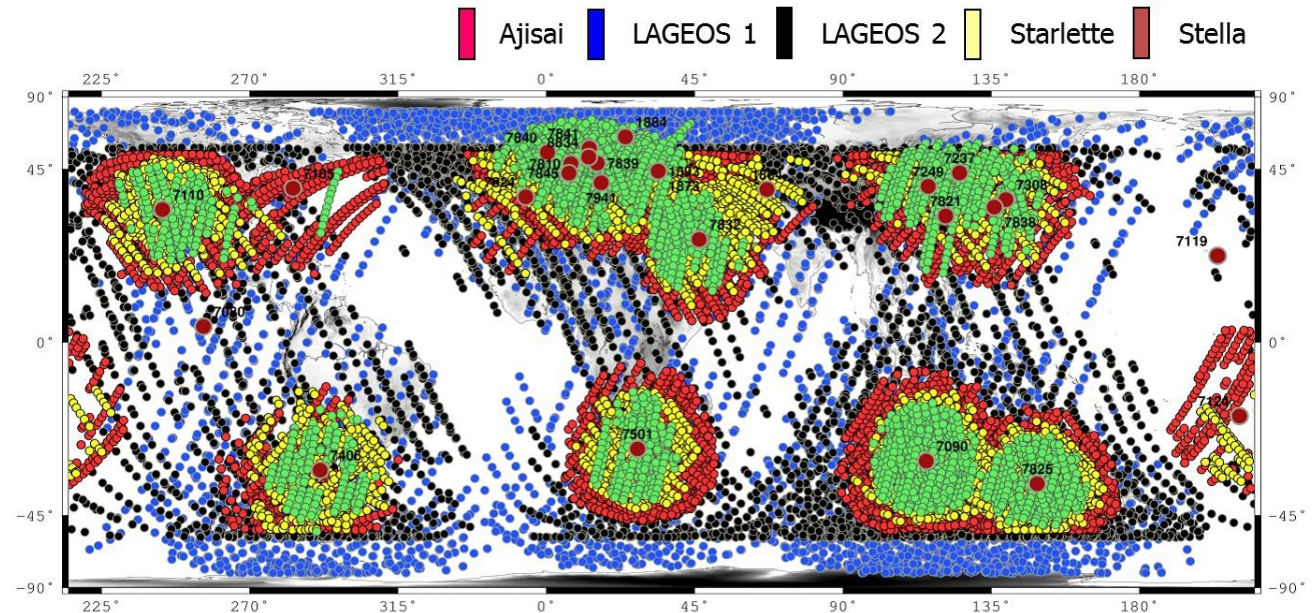
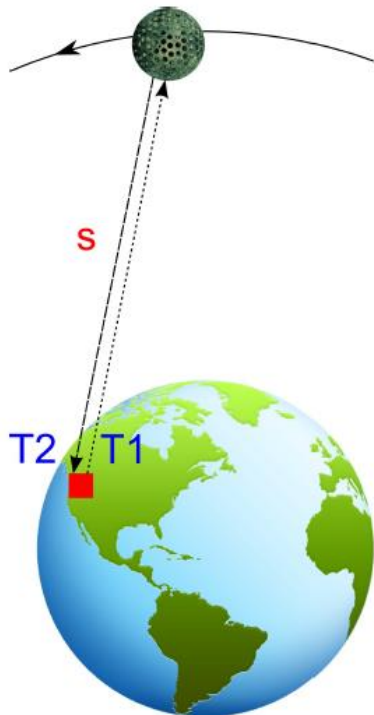
Pre CHAMP era

Space geodetic observation techniques

Optical:



SLR:



courtesy Oliver Baur

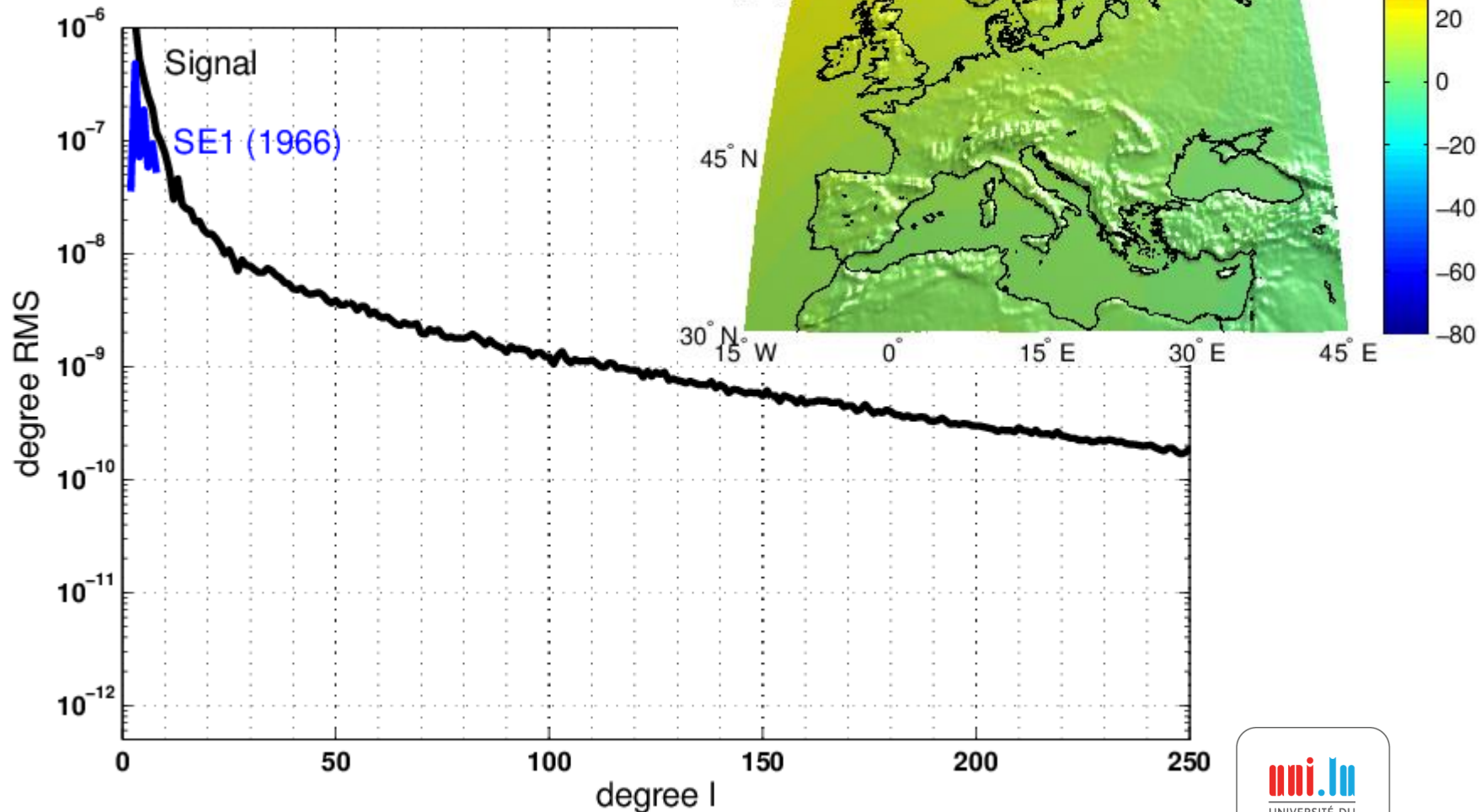
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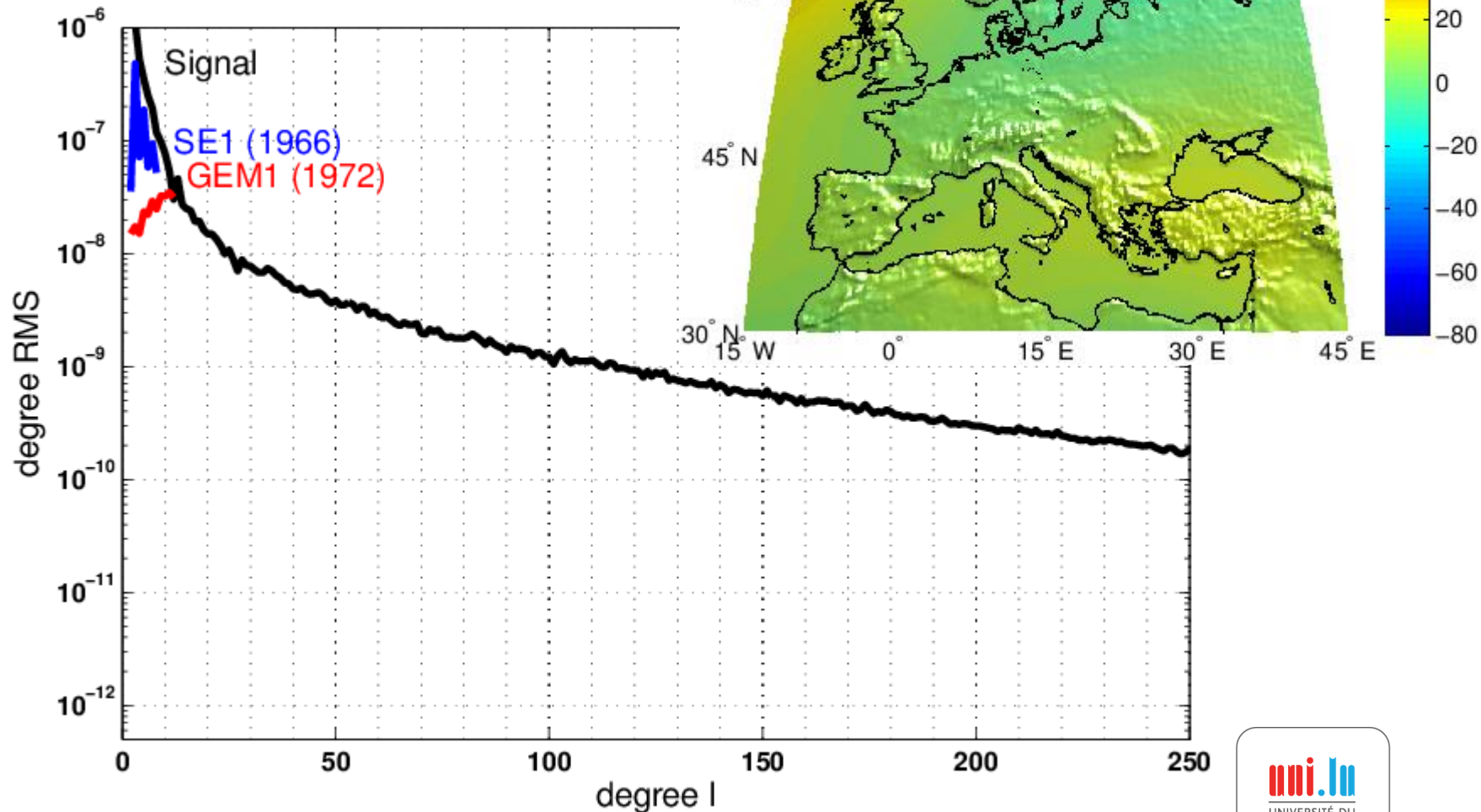
Development of the gravity field precision and resolution

1966: $L_{Max} = 8$
 $\lambda = 5000km$



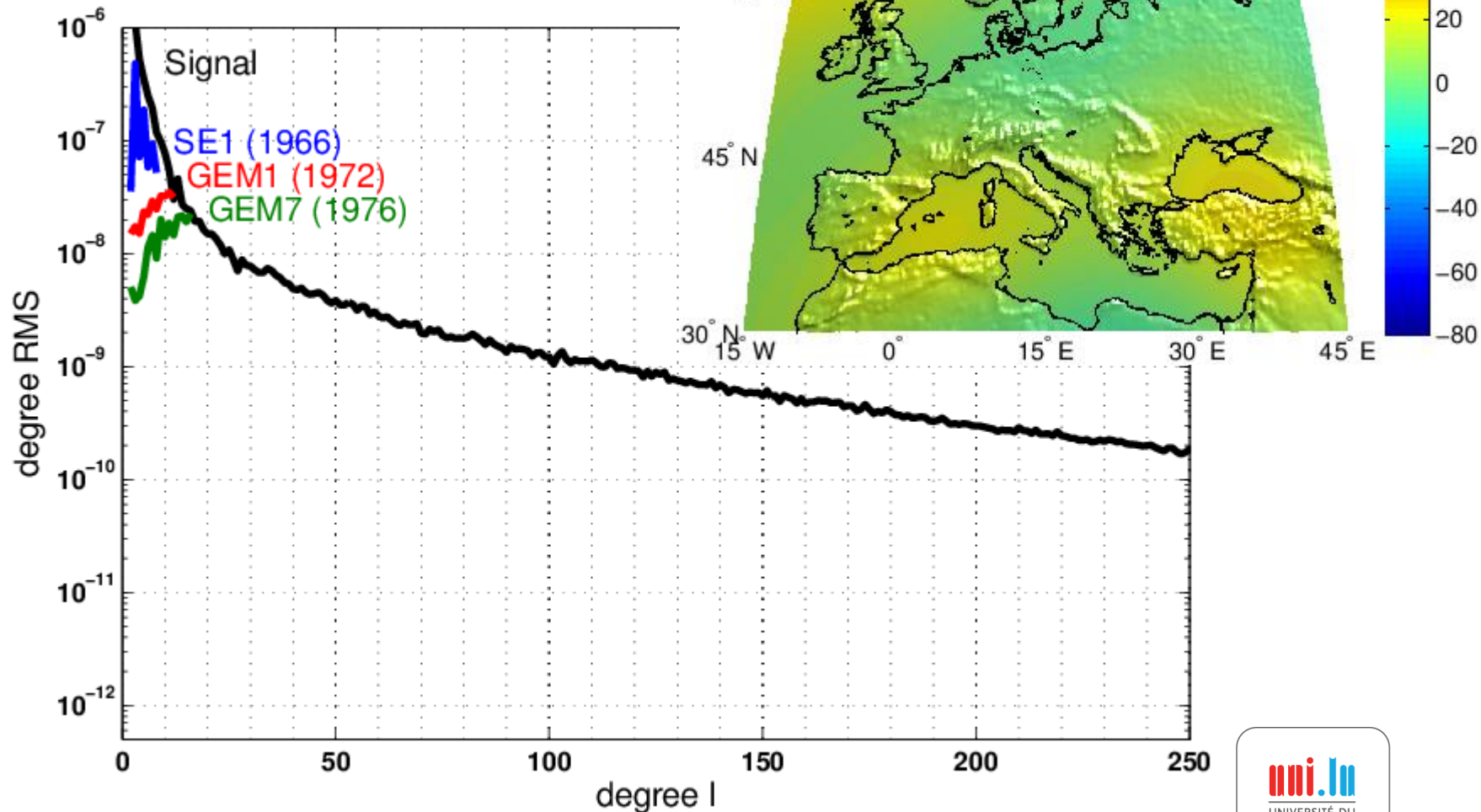
Development of the gravity field precision and resolution

1972: $L_{Max} = 12$
 $\lambda = 3200km$



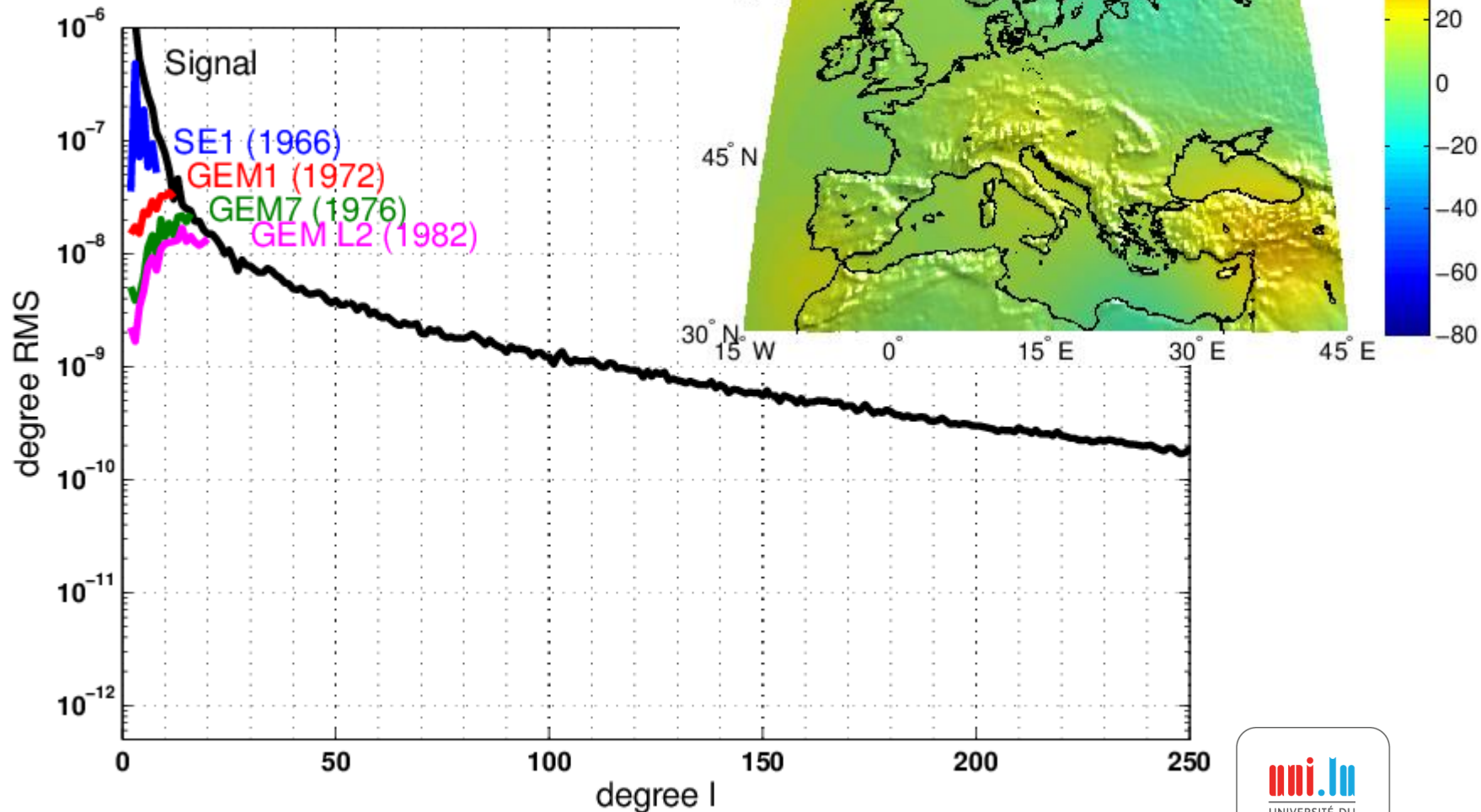
Development of the gravity field precision and resolution

1976: $L_{Max} = 16$
 $\lambda = 2500km$



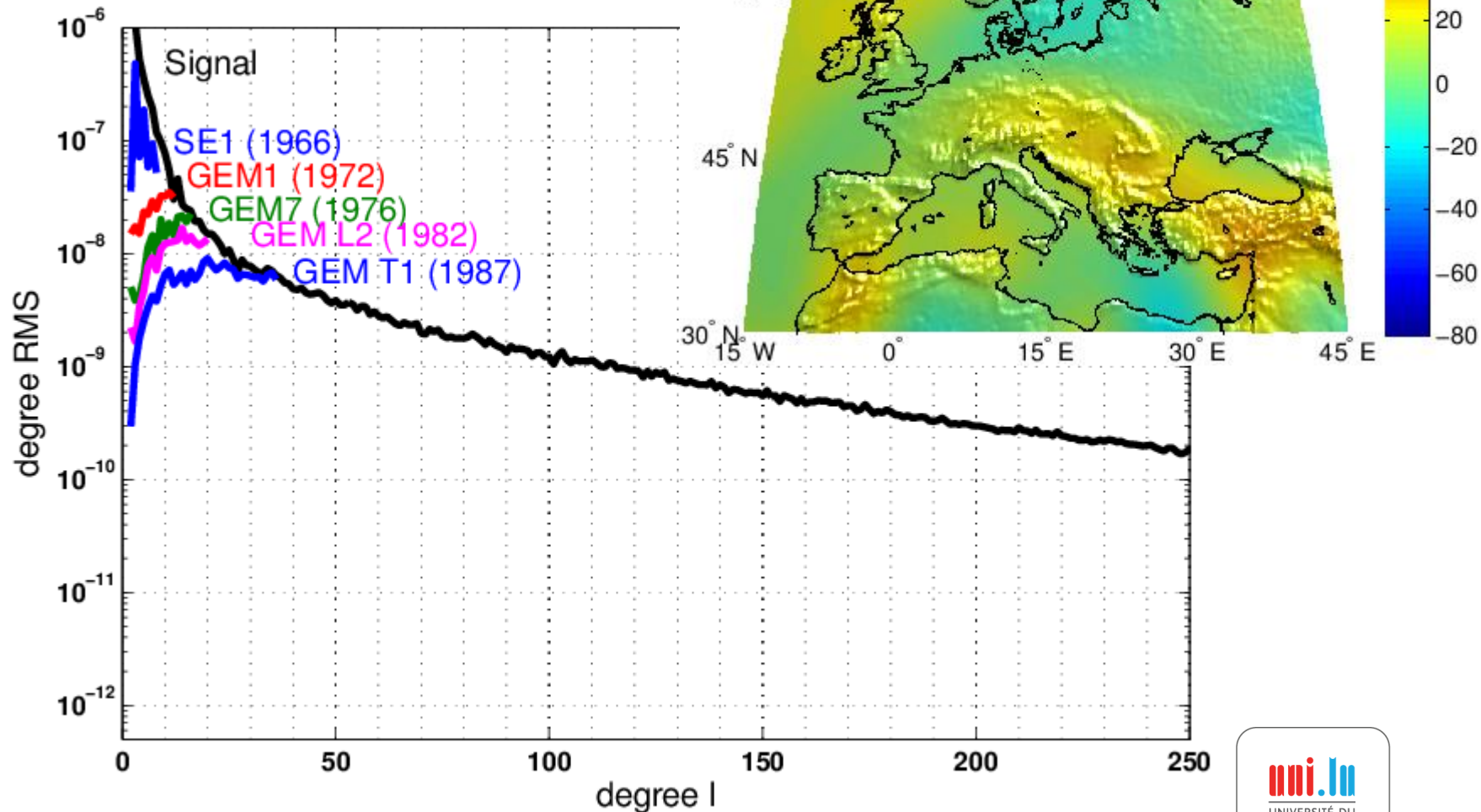
Development of the gravity field precision and resolution

1982: $L_{Max} = 20$
 $\lambda = 2000km$



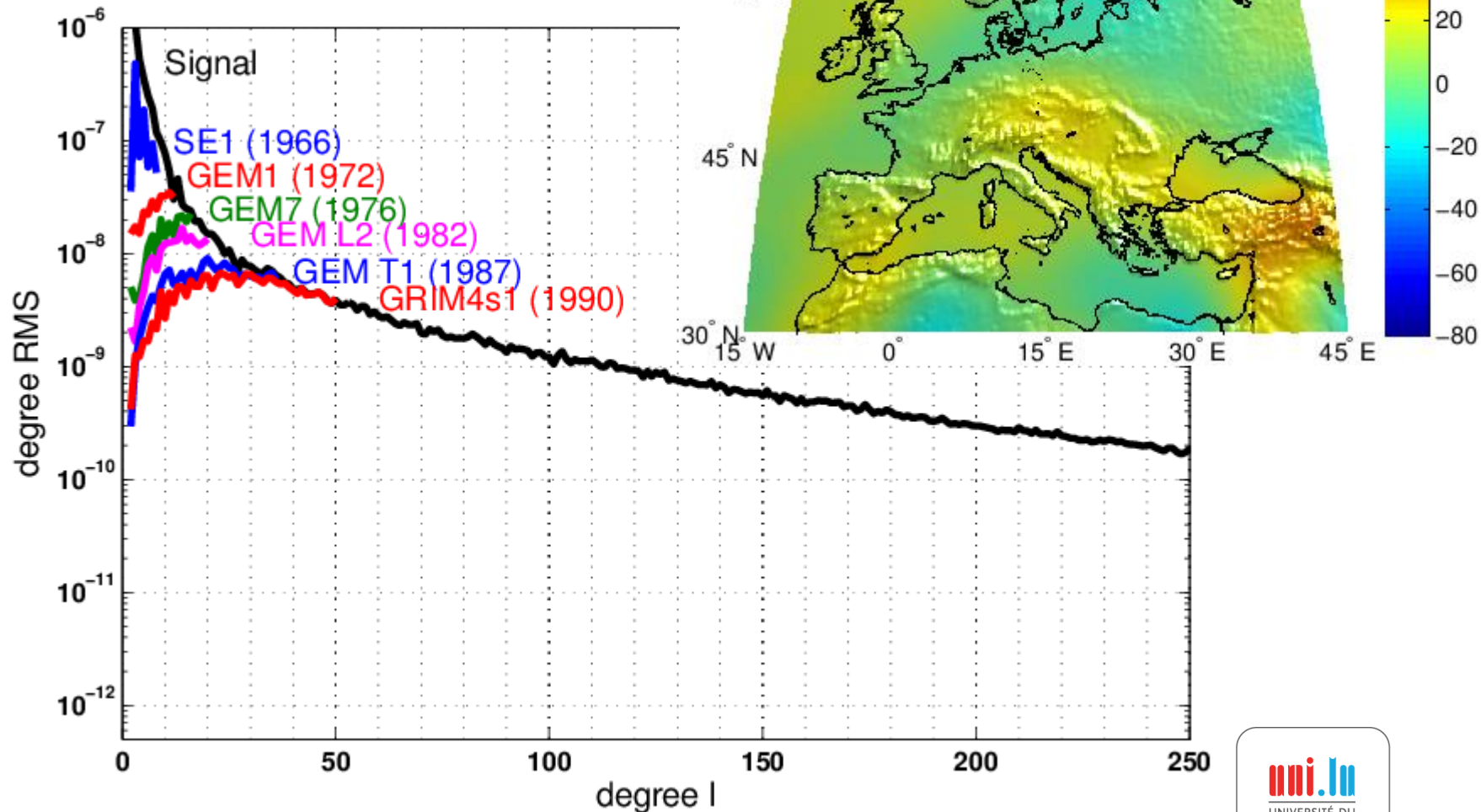
Development of the gravity field precision and resolution

$$1987: L_{Max} = 36$$
$$\lambda = 1110km$$



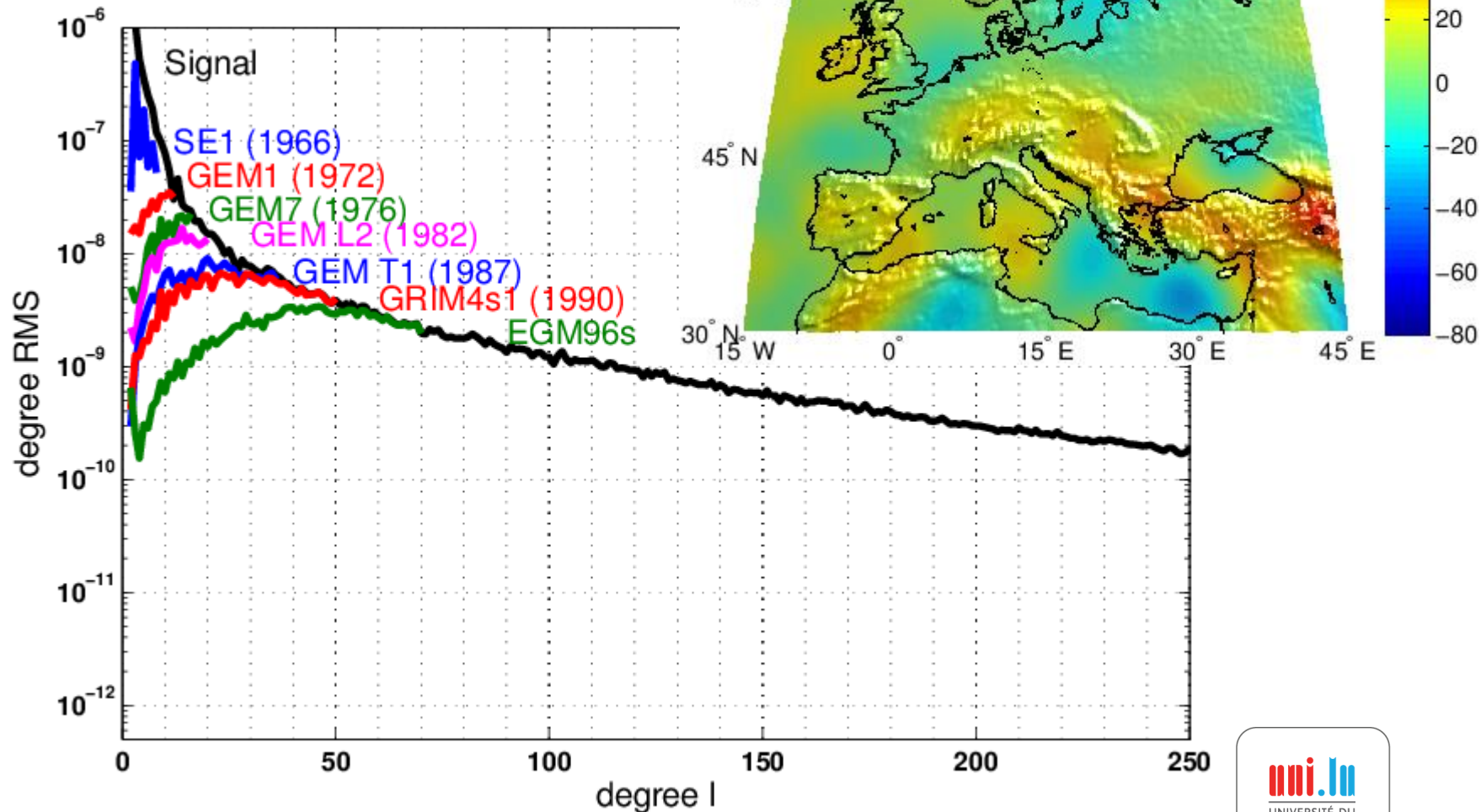
Development of the gravity field precision and resolution

1990: $L_{Max} = 50$
 $\lambda = 800km$



Development of the gravity field precision and resolution

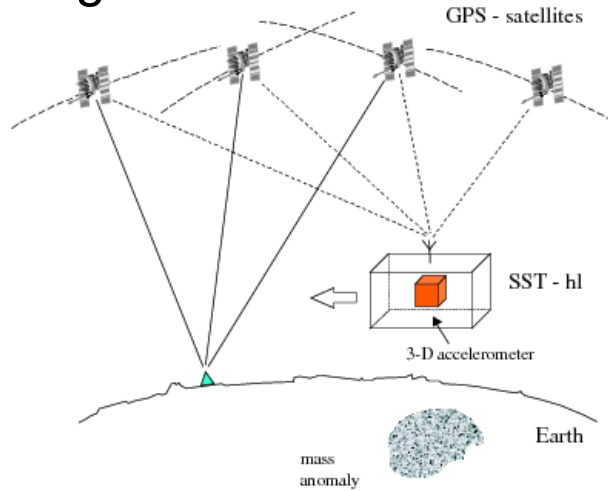
1996: $L_{Max} = 70$
 $\lambda = 570km$



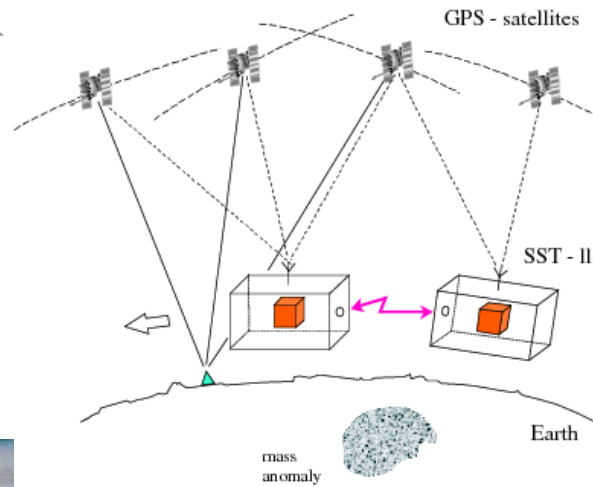
The Decade of the Geopotentials - the concepts

Satellite missions

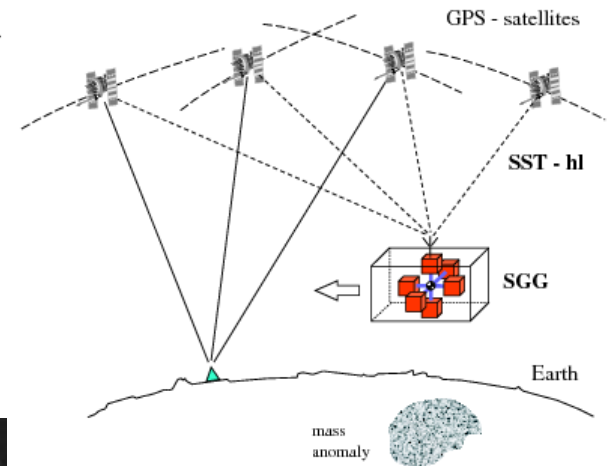
High-low SST



Low-low SST

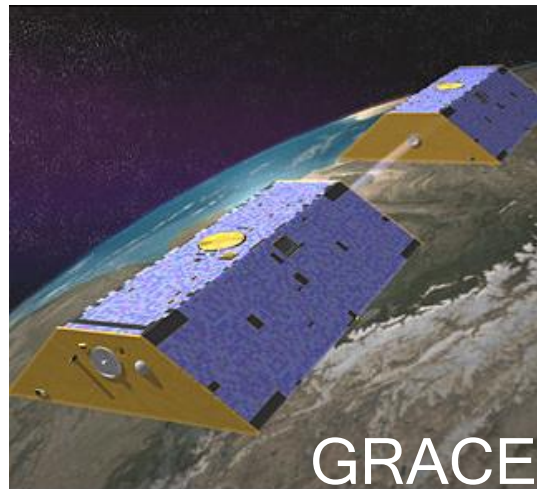


Gradiometry



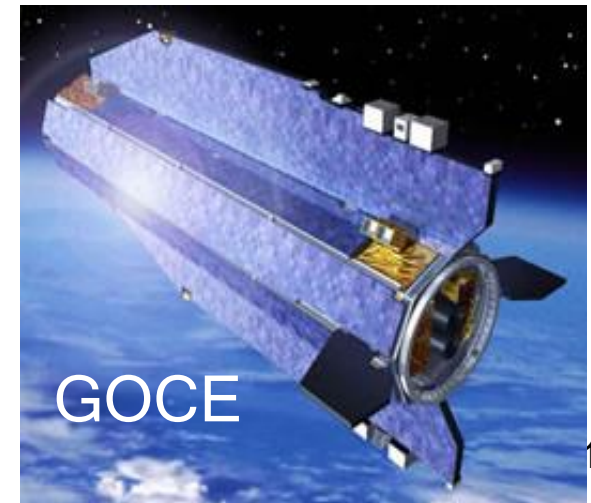
CHAMP

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GRACE

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GOCE

© ESA

CHAMP

Satellite system CHAMP

CHAMP = CHAllenging Minisatellite Payload

- Initial orbit height: ~ 485 km
- Inclination: ~ 87.5°
- Key technologies:
 - GPS
 - Accelerometer
 - (Magnetometers)
- Observation quantity:
 - Position by GPS
 - Non-gravitational forces by accelerometers

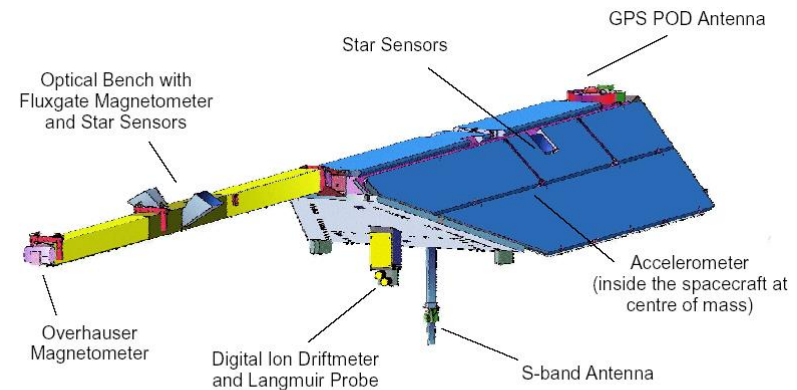
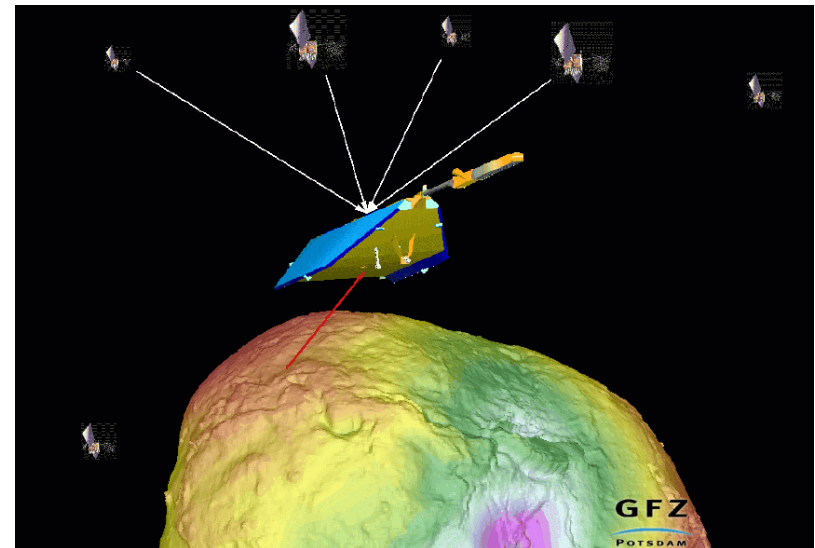


Figure 4-1: Front side view of CHAMP with location of instruments



Newton's equation of motion

$$F = G \frac{m_1 m_2}{r^2}$$

Newton's equation of motion

$$F = G \frac{m_1 m_2}{r^2} \rightarrow F = m_1 \frac{GM}{r^2}$$

Newton's equation of motion

$$F = G \frac{m_1 m_2}{r^2} \rightarrow F = m_1 \frac{GM}{r^2} \rightarrow F \approx a$$

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Observation: \vec{x} (position)

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Differentiation: $\frac{\partial^2 \vec{x}}{\partial t^2} = \ddot{\vec{x}}$ (acceleration)

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$$\vec{F} = \vec{a} = \ddot{\vec{x}}$$

Newton's equation of motion

$$F = G \frac{m_1 m_2}{r^2} \rightarrow F = m_1 \frac{GM}{r^2} \rightarrow F \approx a$$

Observation: \vec{x} (position)

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$$\vec{F} = \vec{a} = \ddot{\vec{x}}$$

$$\vec{f}_{\text{Grav}} = \ddot{\vec{x}} - \vec{f}_{\text{3rdBody}} - \vec{f}_{\text{Tides}} - \vec{f}_{\text{Rel}} - \vec{f}_{\text{NonGrav}}$$

Newton's equation of motion

$$F = G \frac{m_1 m_2}{r^2} \rightarrow F = m_1 \frac{GM}{r^2} \rightarrow F \approx a$$

Observation: \vec{x} (position)

Differentiation: $\frac{\partial^2 \vec{x}}{\partial t^2} = \ddot{\vec{x}}$ (acceleration)

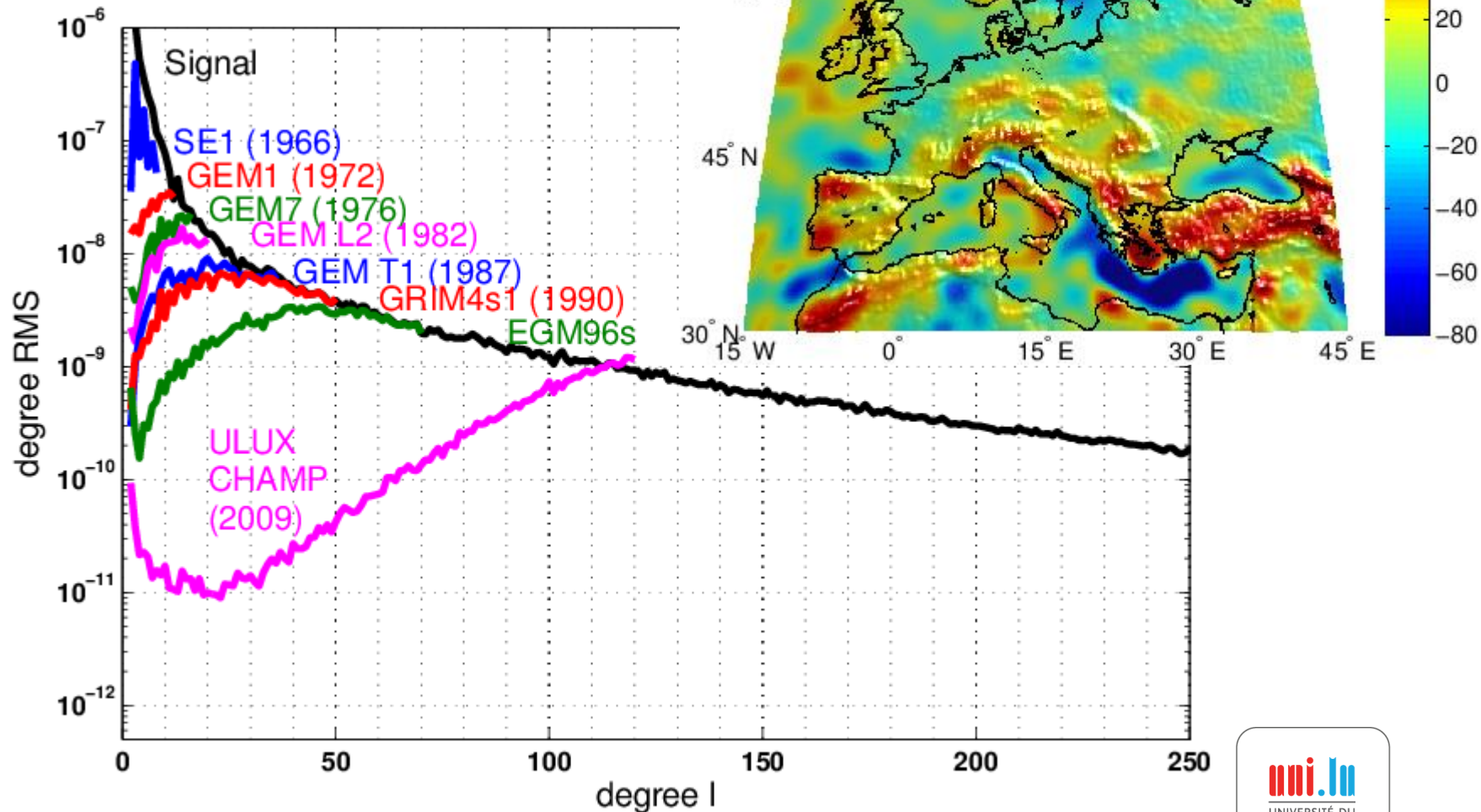
$$\vec{F} = \vec{a} = \ddot{\vec{x}}$$

$$\vec{f}_{\text{Grav}} = \ddot{\vec{x}} - \vec{f}_{\text{3rdBody}} - \vec{f}_{\text{Tides}} - \vec{f}_{\text{Rel}} - \vec{f}_{\text{NonGrav}}$$

$$\nabla V = \ddot{\vec{x}} - \vec{f}_{\text{3rdBody}} - \vec{f}_{\text{Tides}} - \vec{f}_{\text{Rel}} - \vec{f}_{\text{NonGrav}}$$

GAIN due to CHAMP

$$2010: L_{Max} = 120$$
$$\lambda = 330km$$

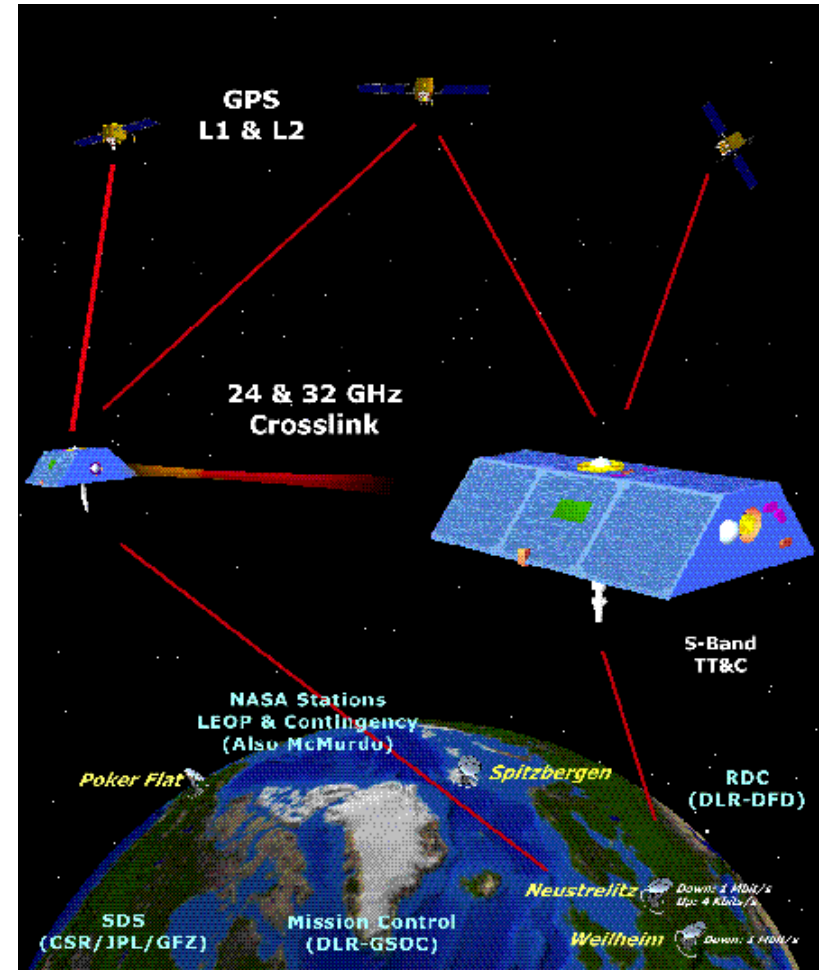


GRACE

Satellite system GRACE

GRACE = Gravity Recovery and Climate Experiment

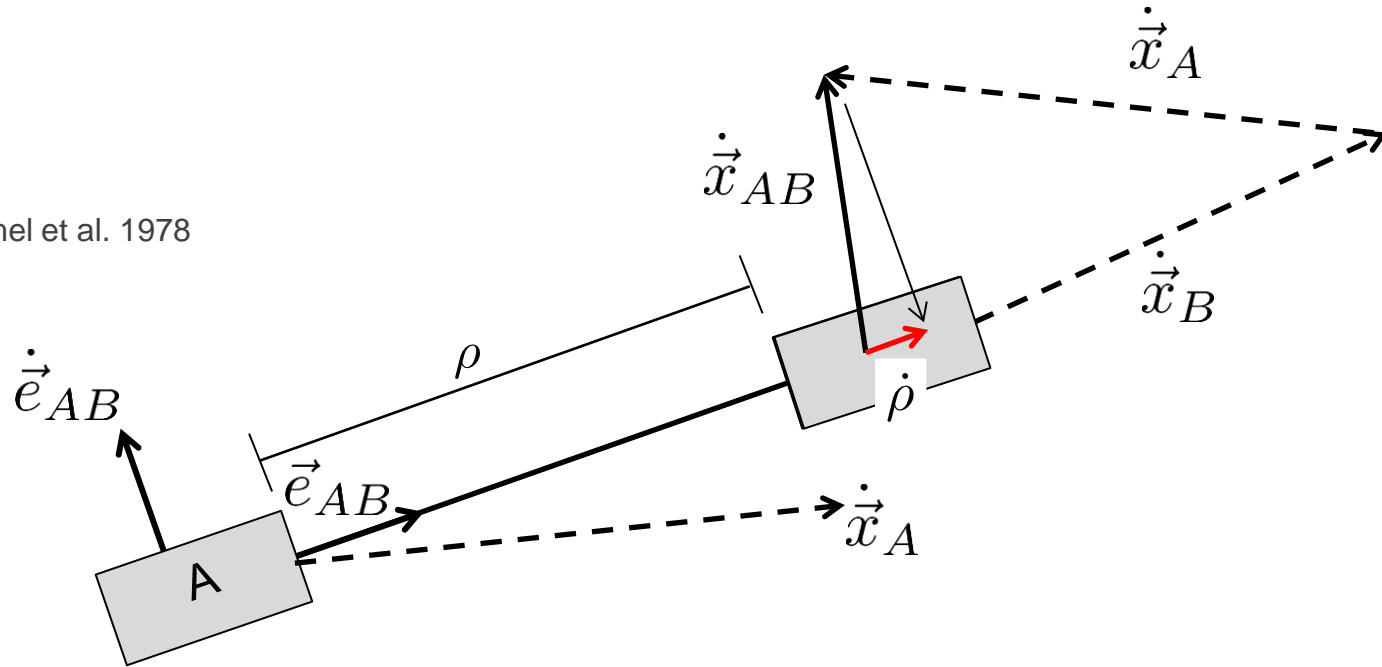
- Initial orbit height: ~ 485 km
- Inclination: ~ 89°
- Key technologies:
 - GPS
 - accelerometer
 - K-Band ranging system
- Observation quantity:
 - distance (range)
 - change of distance (range rate)



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Geometry of the GRACE system

Rummel et al. 1978



Differentiation

Integration

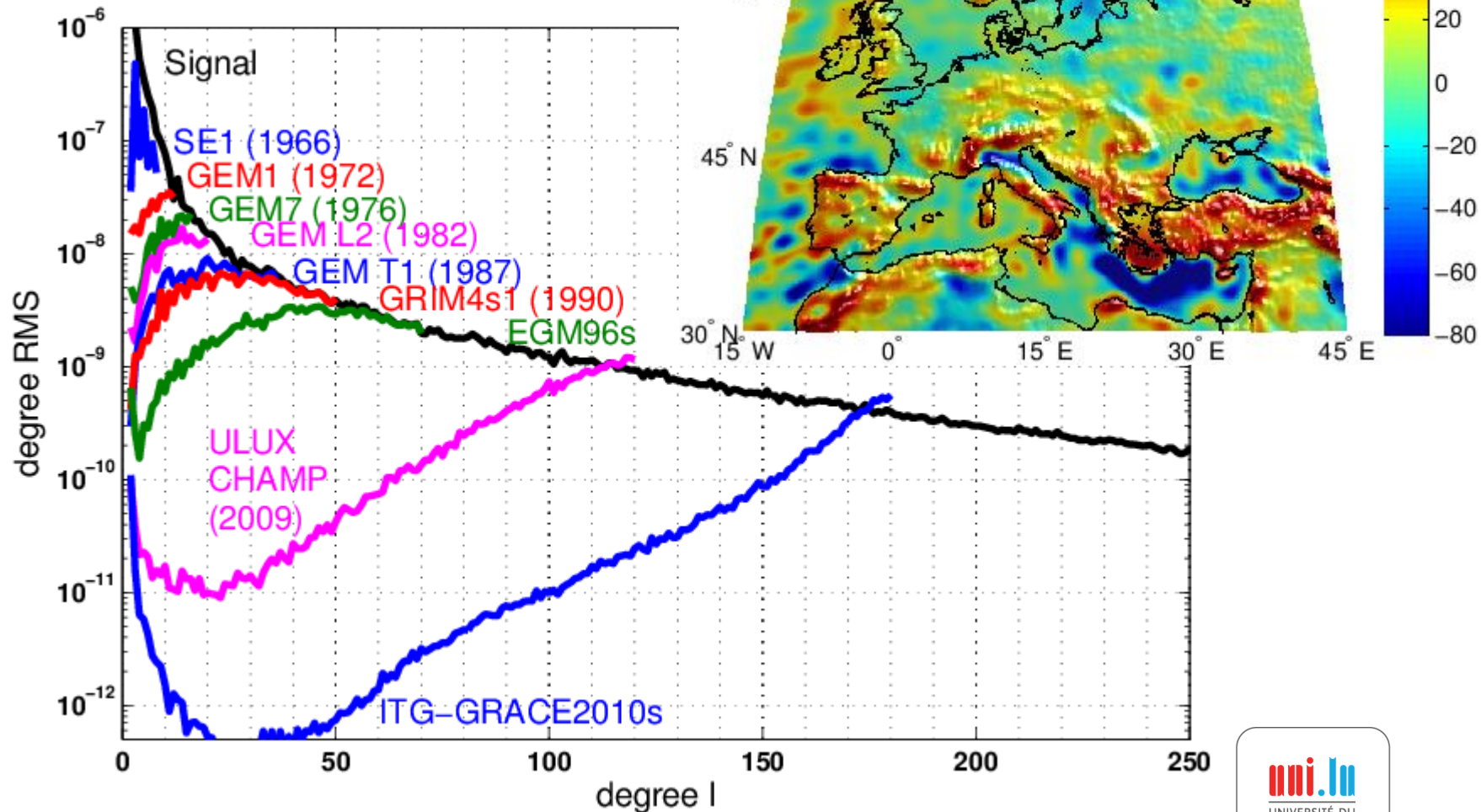
$$\rho = \vec{x}_{AB} \cdot \vec{e}_{AB}$$

$$\dot{\rho} = \dot{\vec{x}}_{AB} \cdot \vec{e}_{AB}$$

$$\ddot{\rho} = \ddot{\vec{x}}_{AB} \cdot \vec{e}_{AB} + \dot{\vec{x}}_{AB} \cdot \dot{\vec{e}}_{AB} = \nabla V_{AB}$$

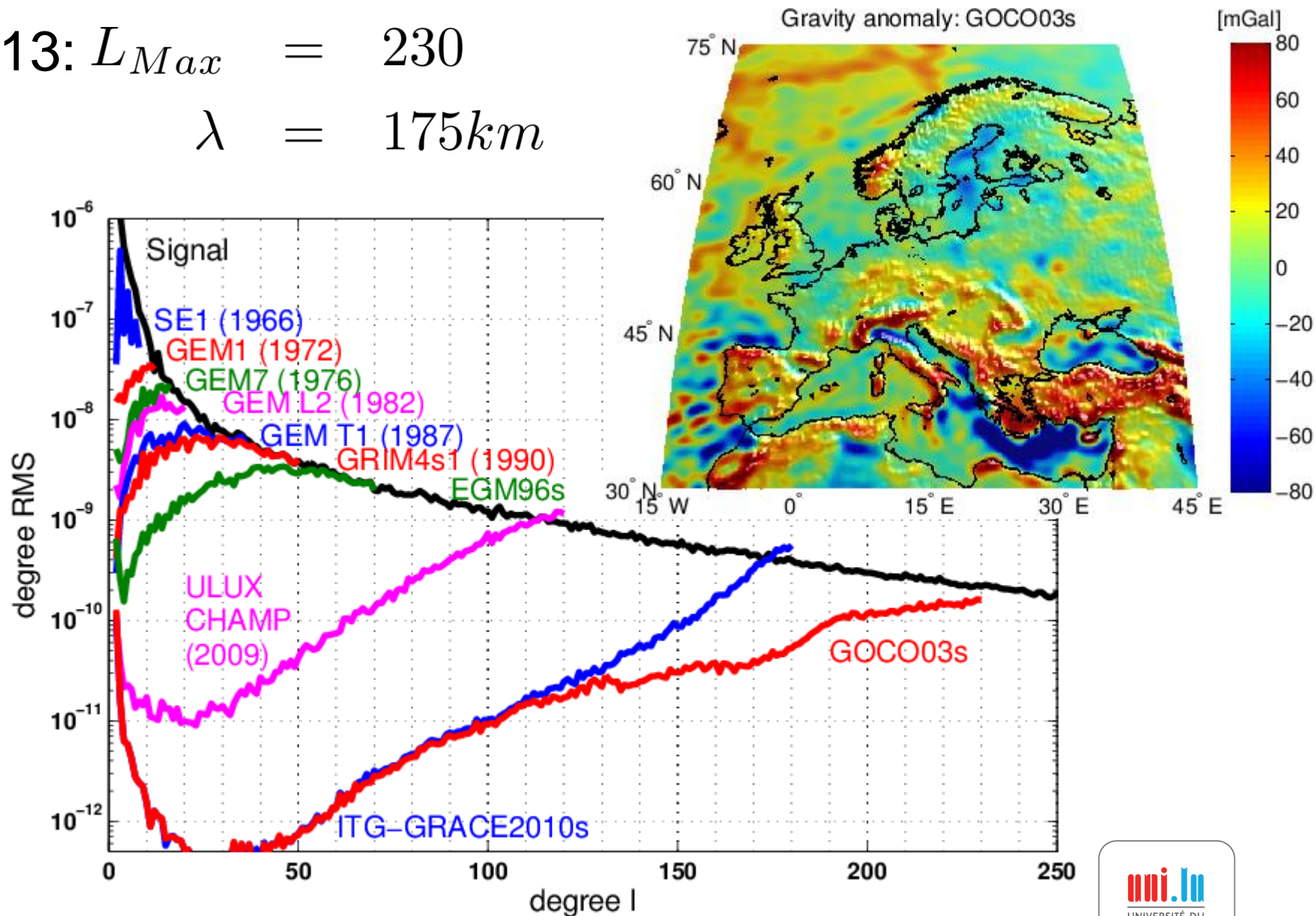
GAIN due to GRACE

$$2013: L_{Max} = 180$$
$$\lambda = 220km$$



GAIN due to GRACE and GOCE

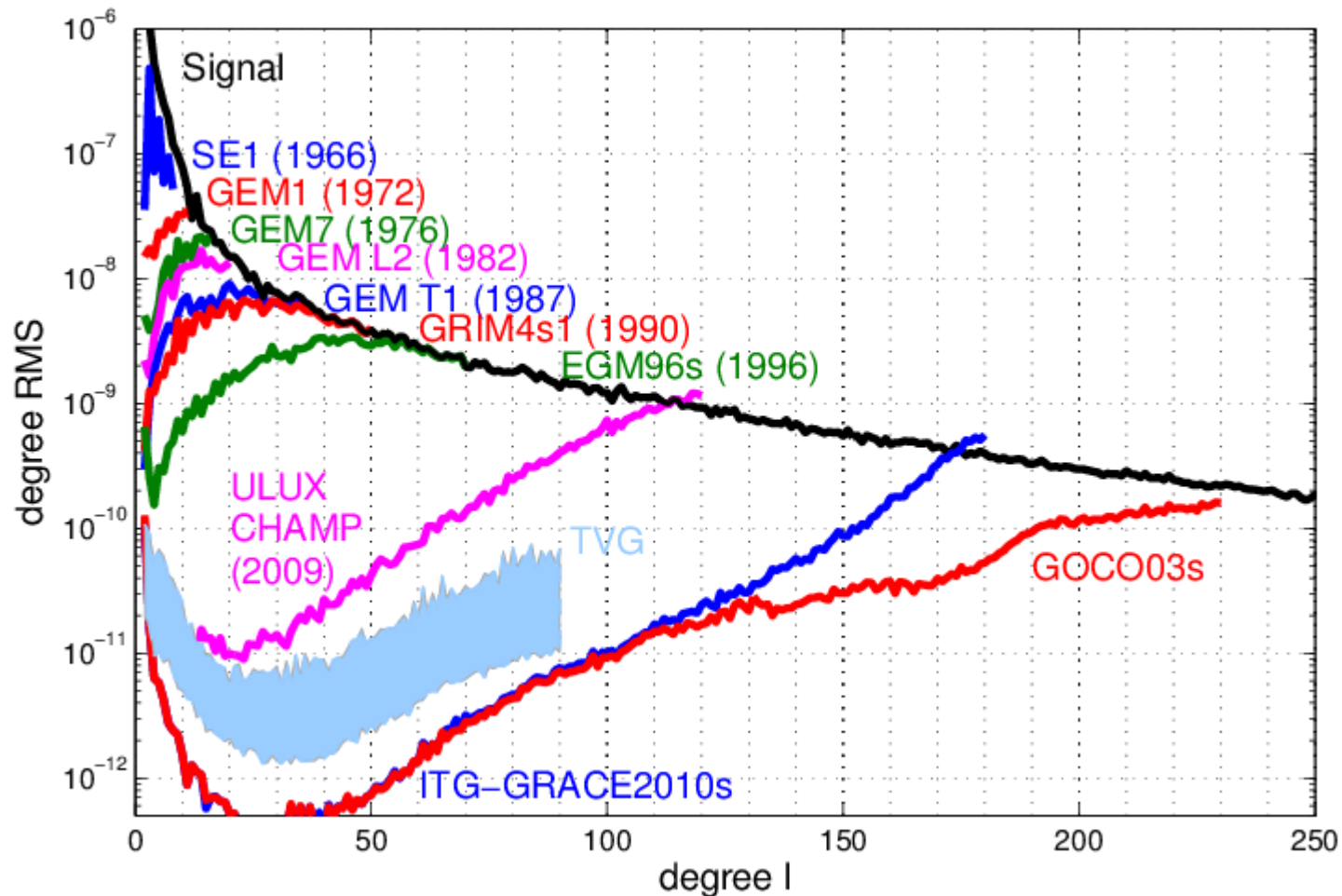
$$2013: L_{Max} = 230$$
$$\lambda = 175km$$



GAIN due to GRACE: time variable gravity (TVG)

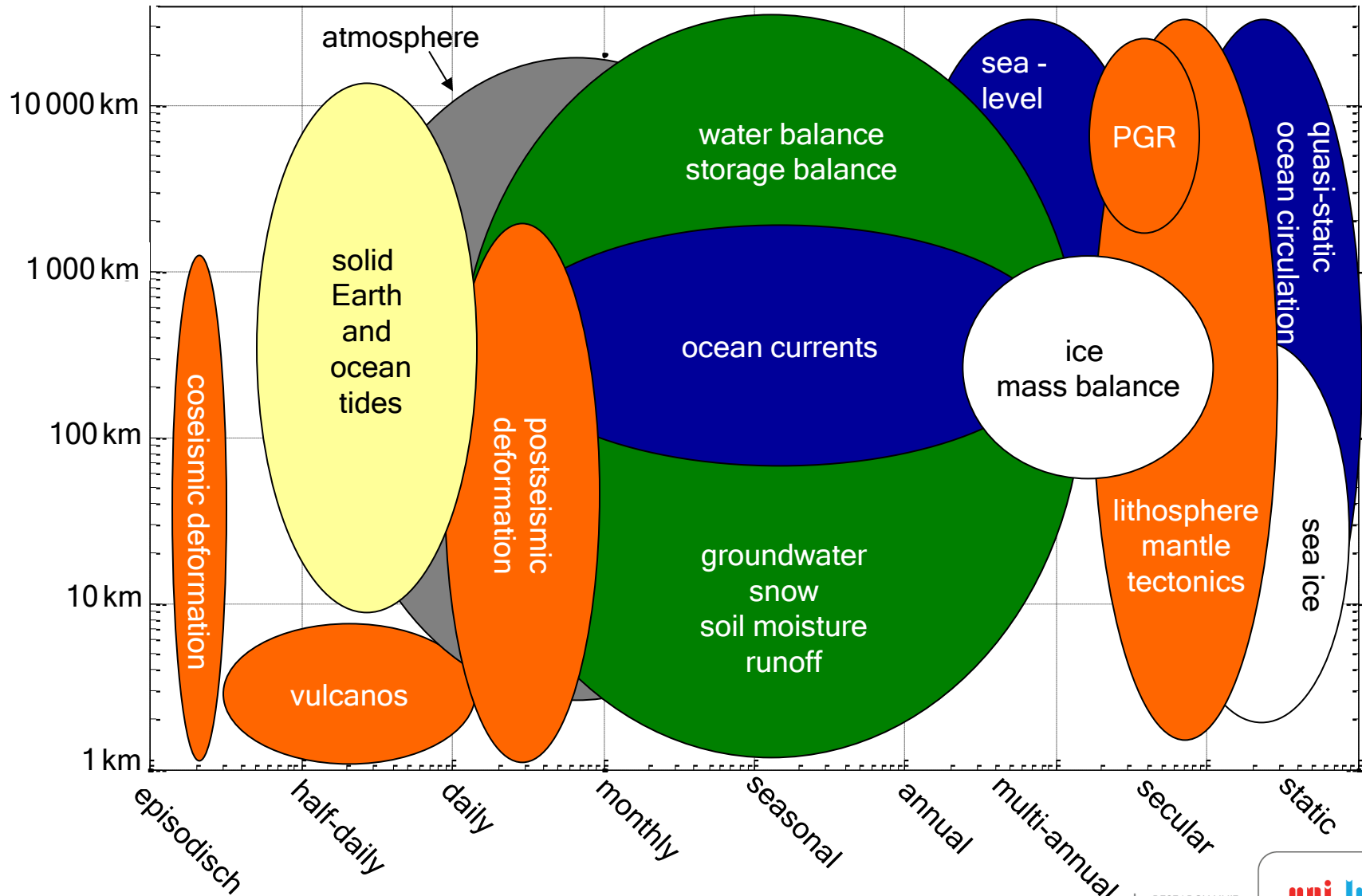
2013: $L_{Max} = 90$

$\lambda = 450km$

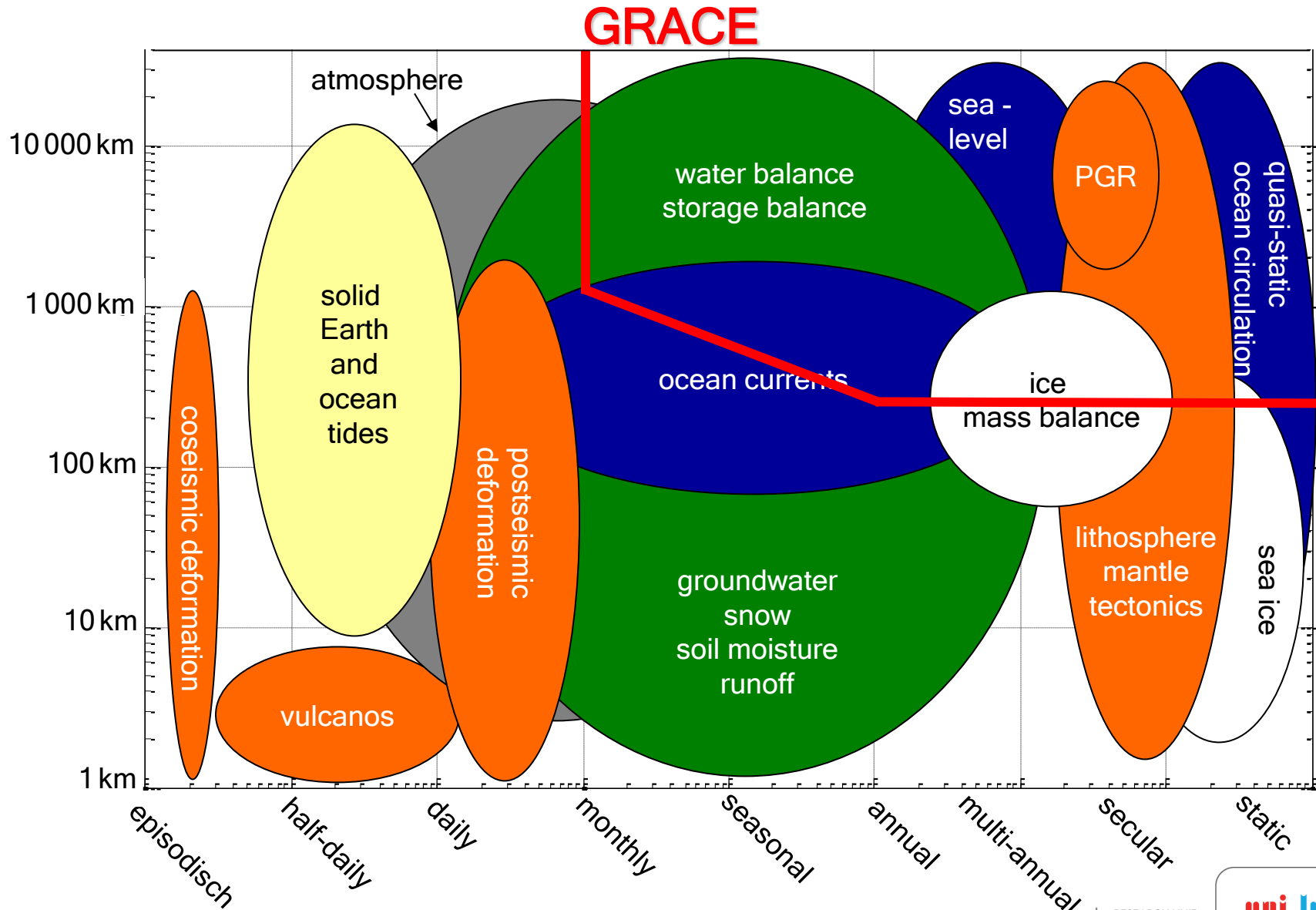


Achievements in terms of the TVG

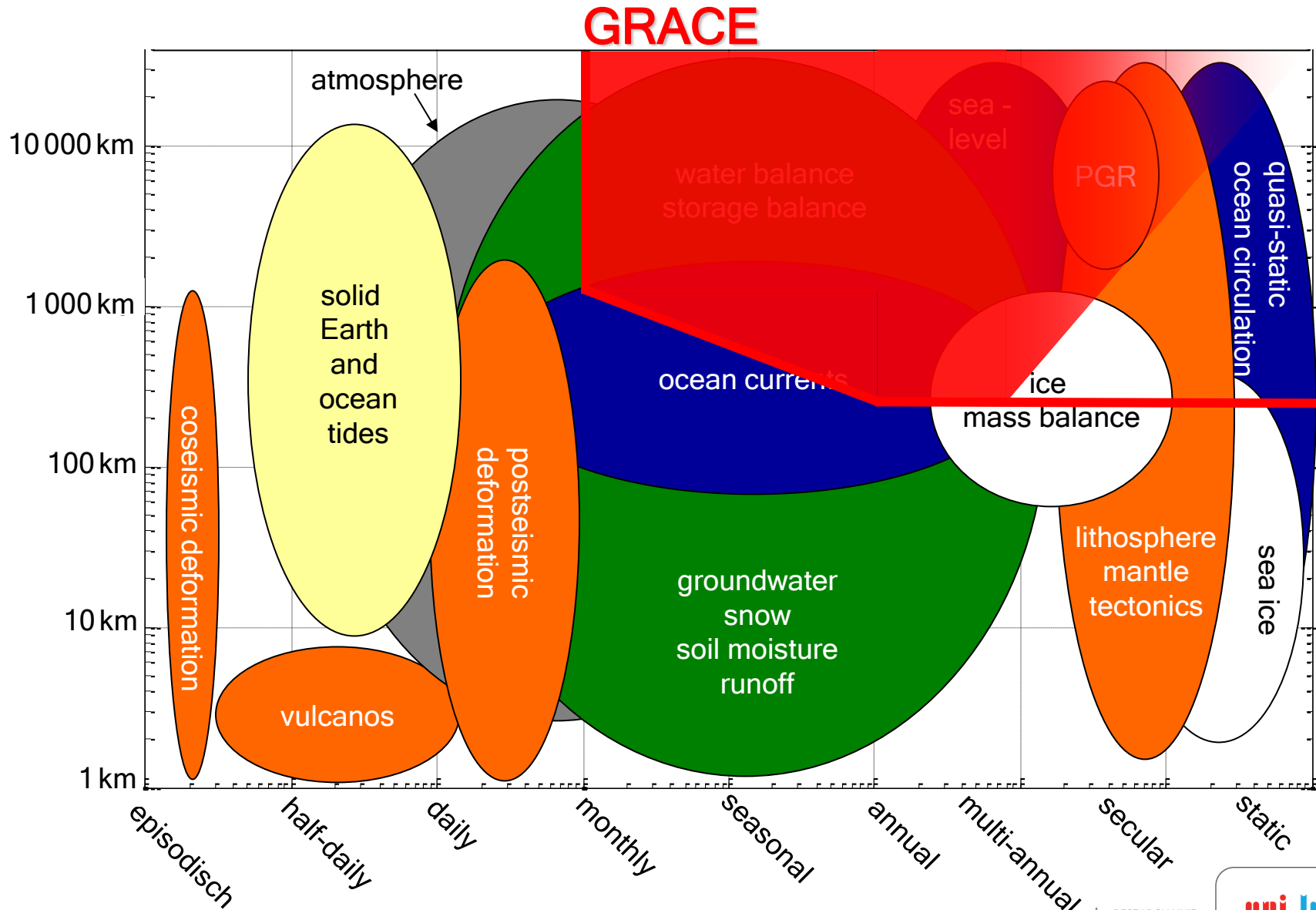
Spatio-temporal resolution ?



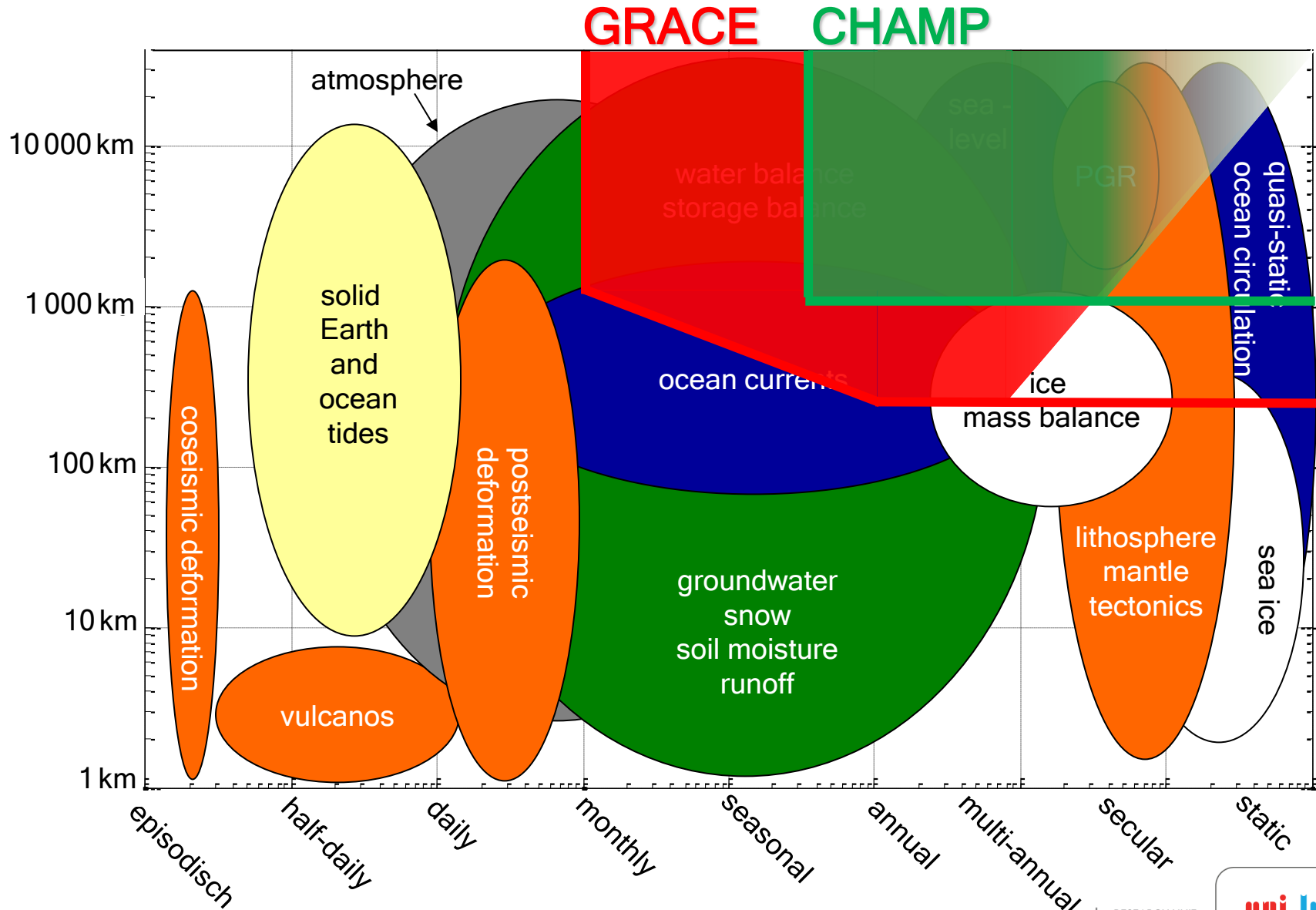
Spatio-temporal resolution ?



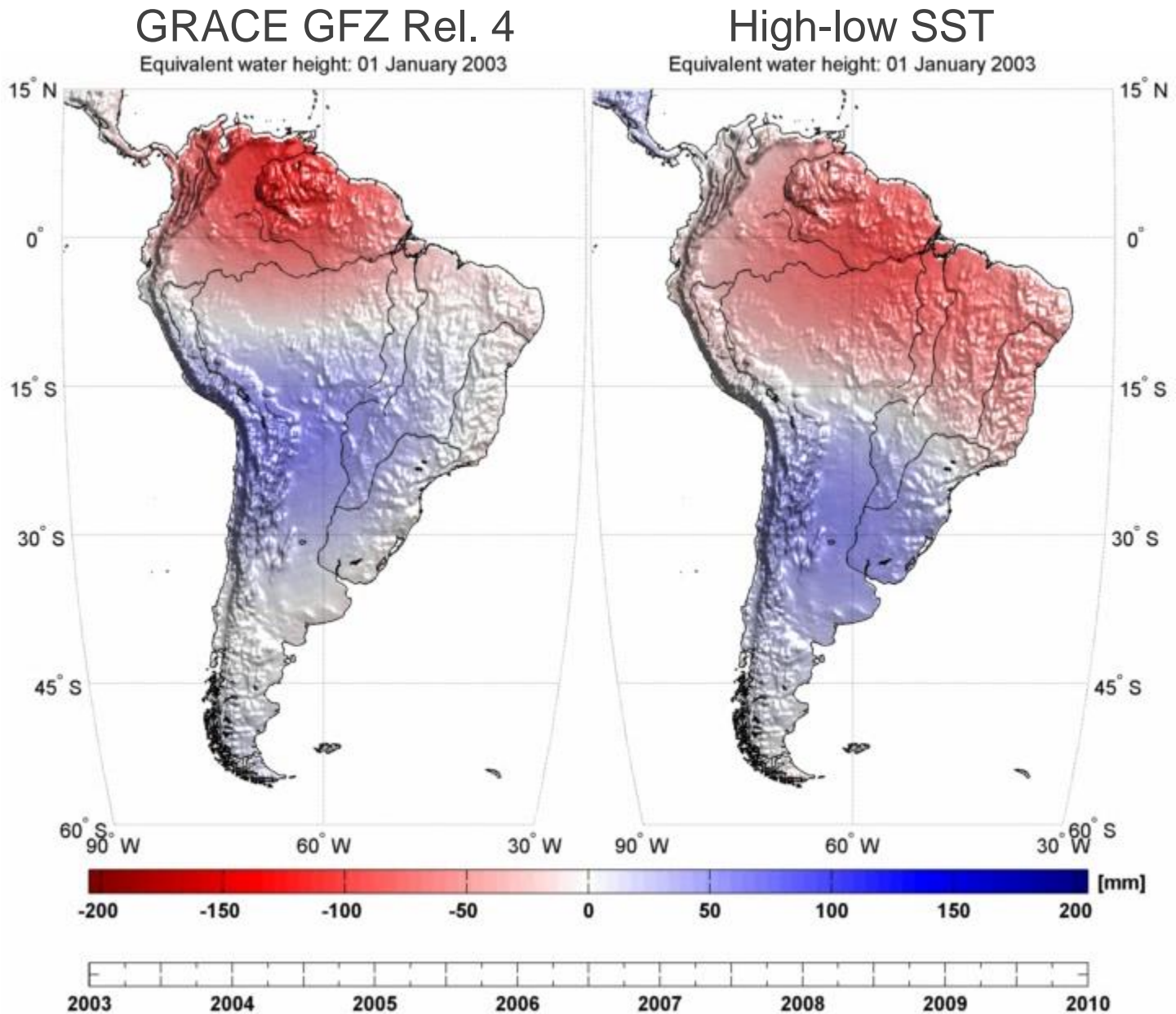
Spatio-temporal resolution ?



Spatio-temporal resolution ?

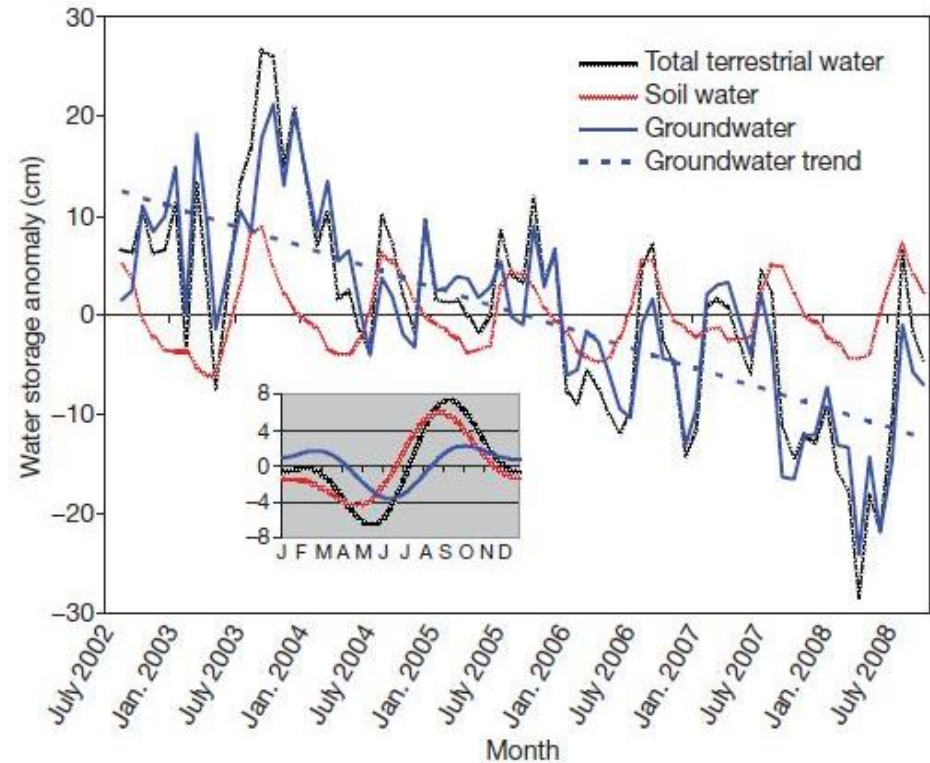
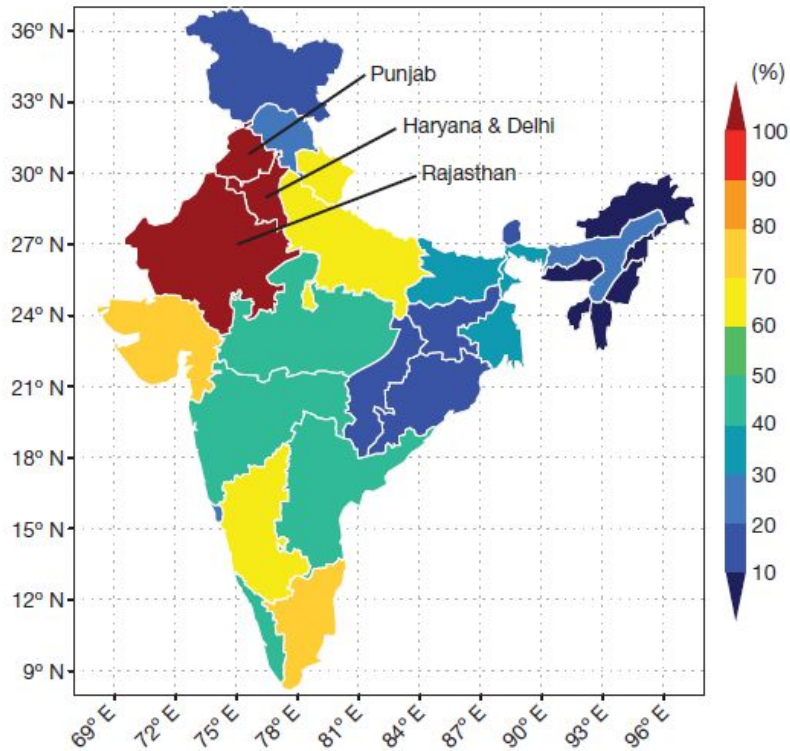


Change in water storage



Water is stressed ...

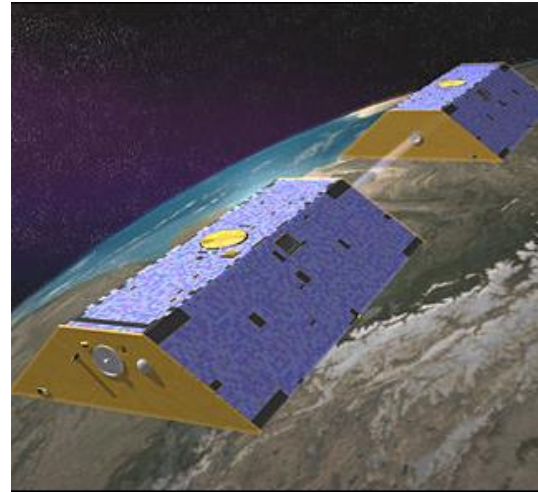
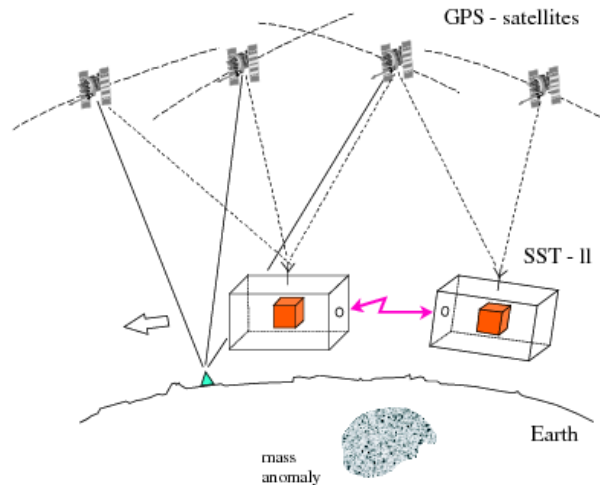
- Water balance in India (Rodell et al., Nature, vol. 460, 2009)



The Future

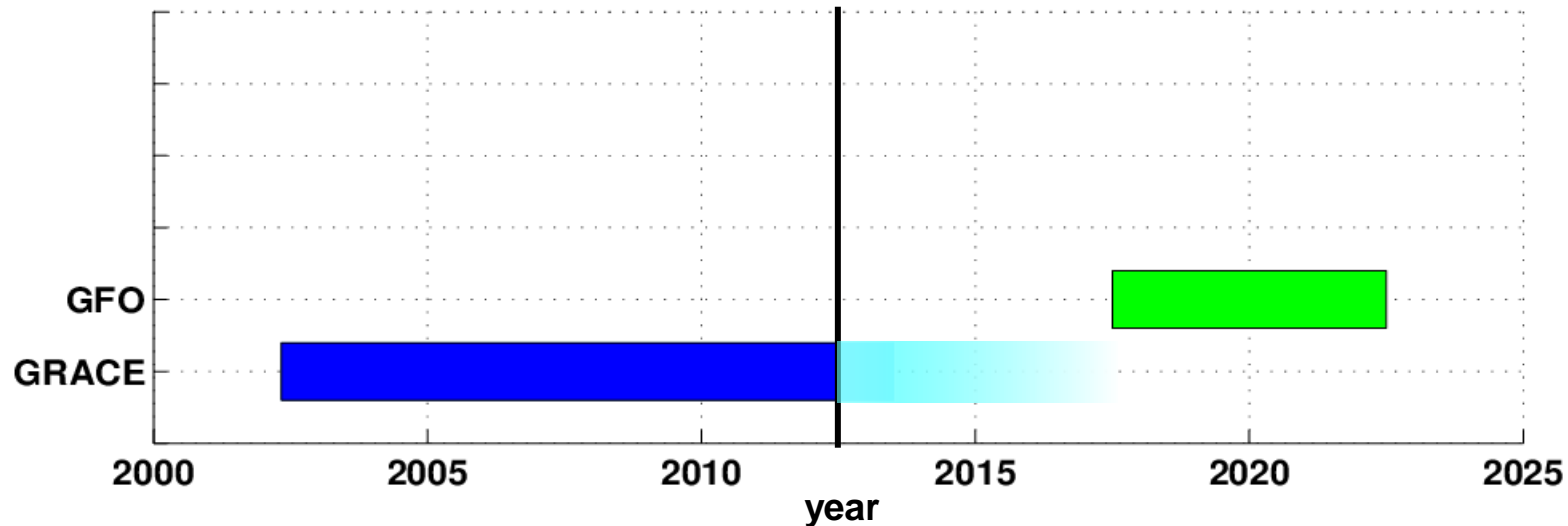
GRACE und GRACE Follow-On (GFO)

Low-low



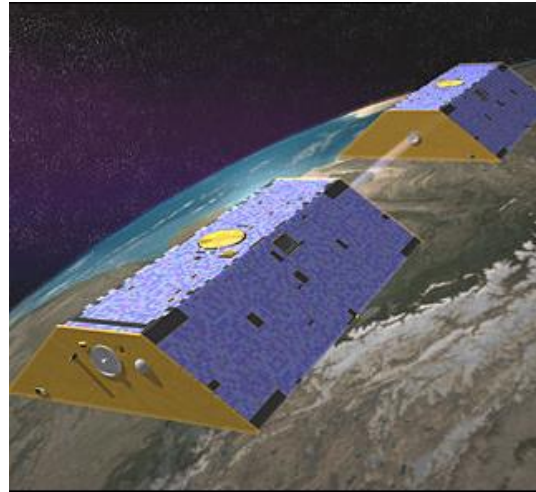
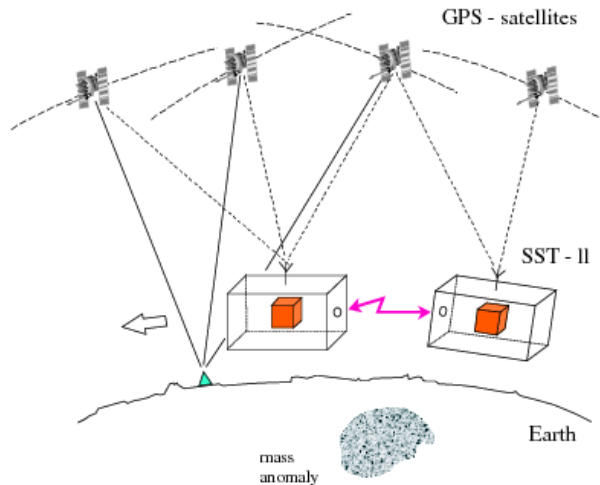
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- K-Band + Laser
- GPS
- Accelerometer



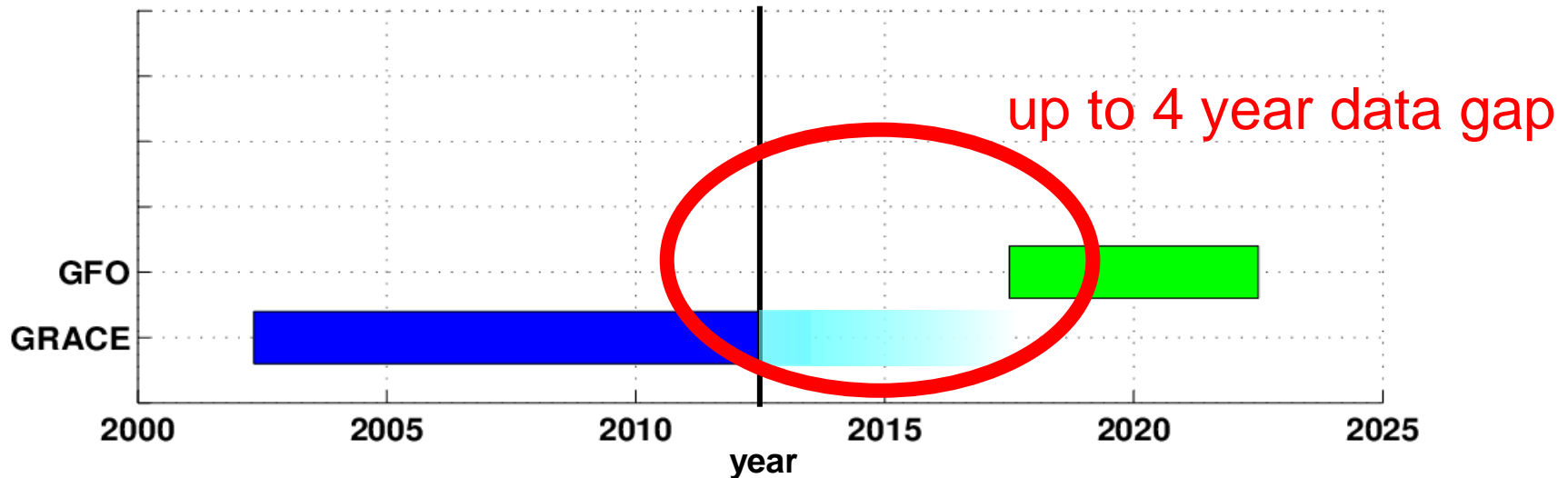
GRACE und GRACE Follow-On (GFO)

Low-low



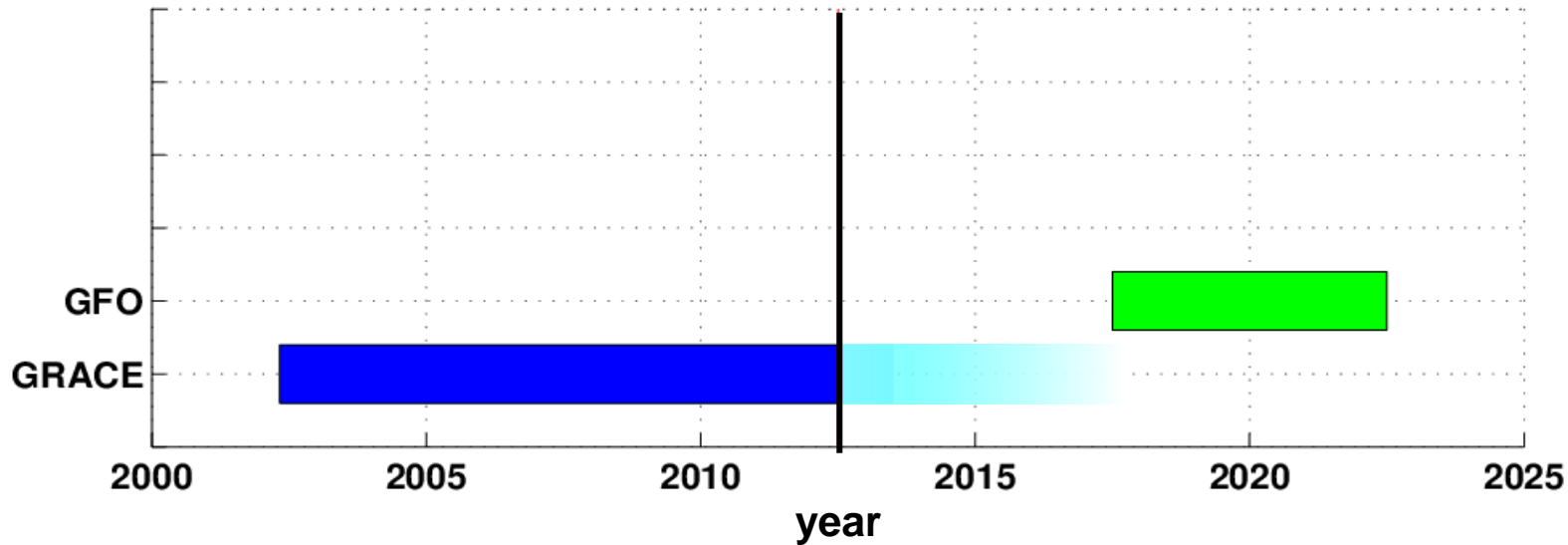
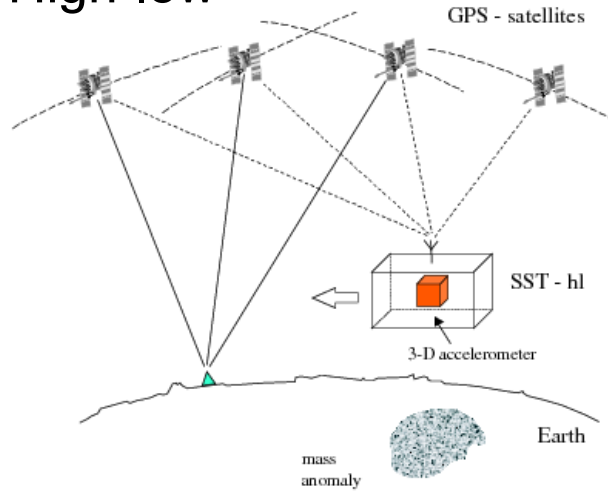
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- K-Band + Laser
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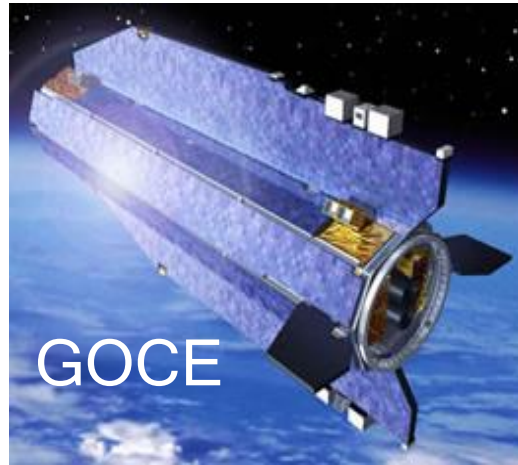
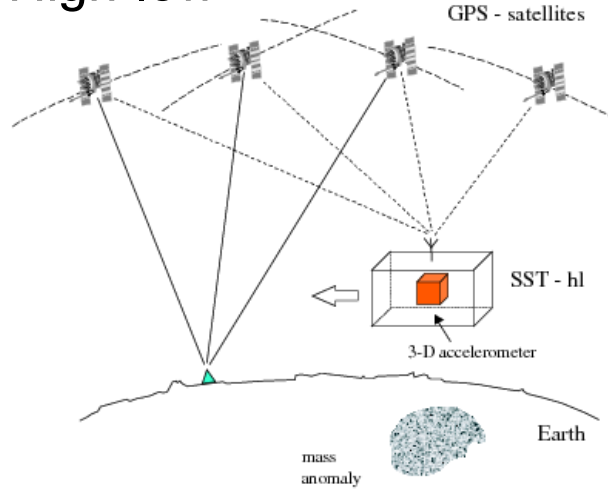
Bridging the gap ...

High-low

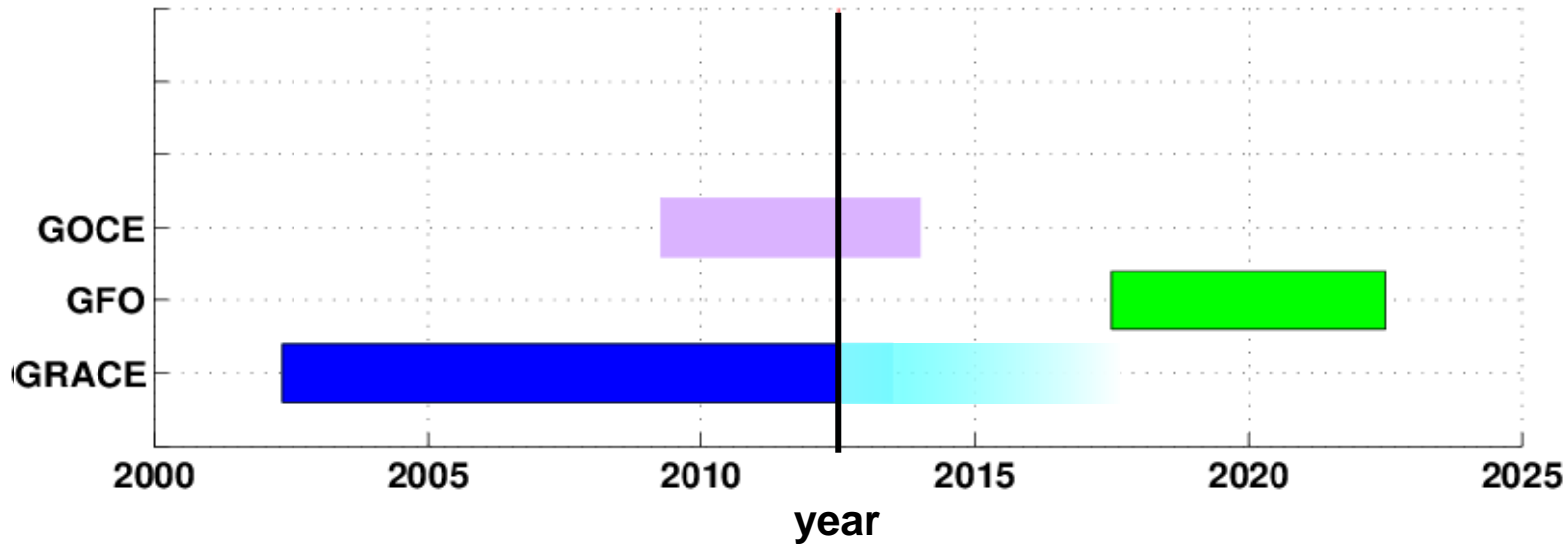


Bridging the gap ...

High-low

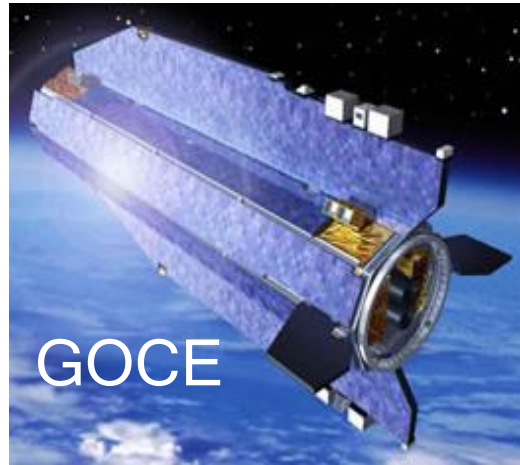
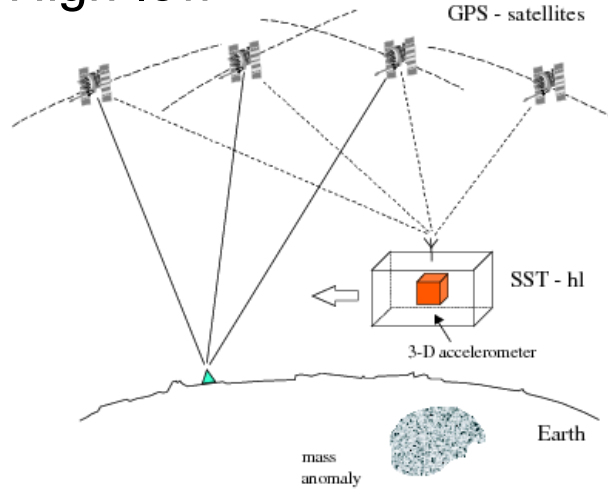


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Bridging the gap ...

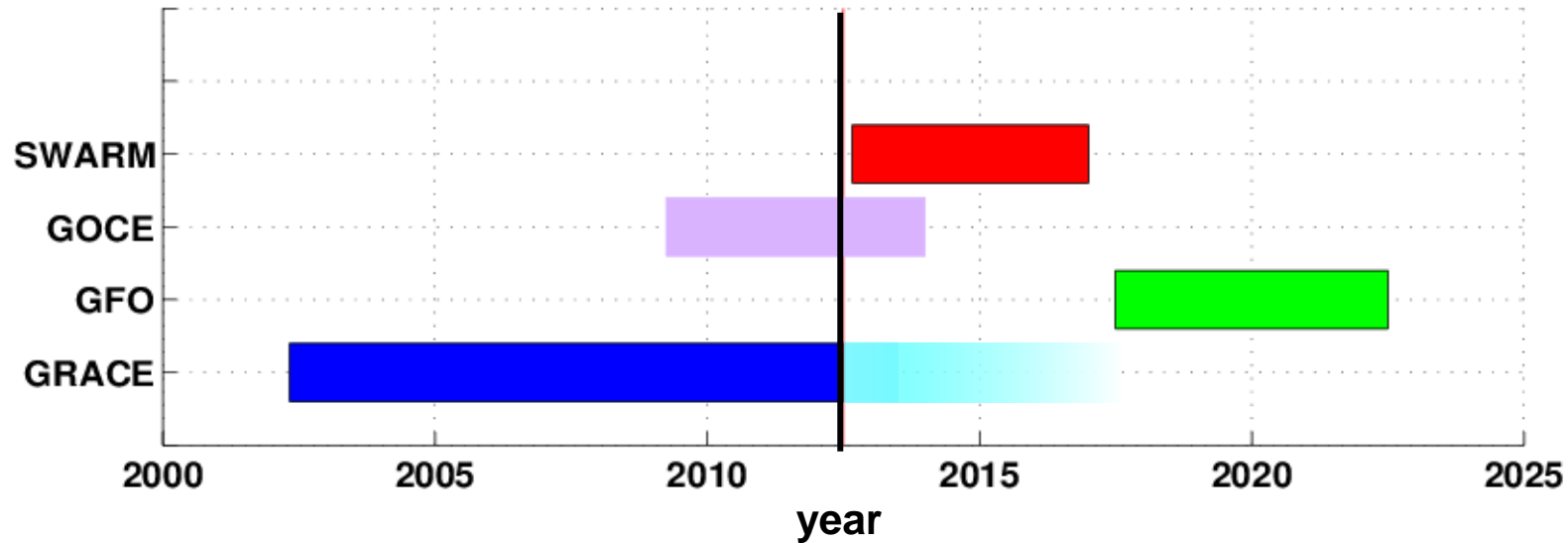
High-low



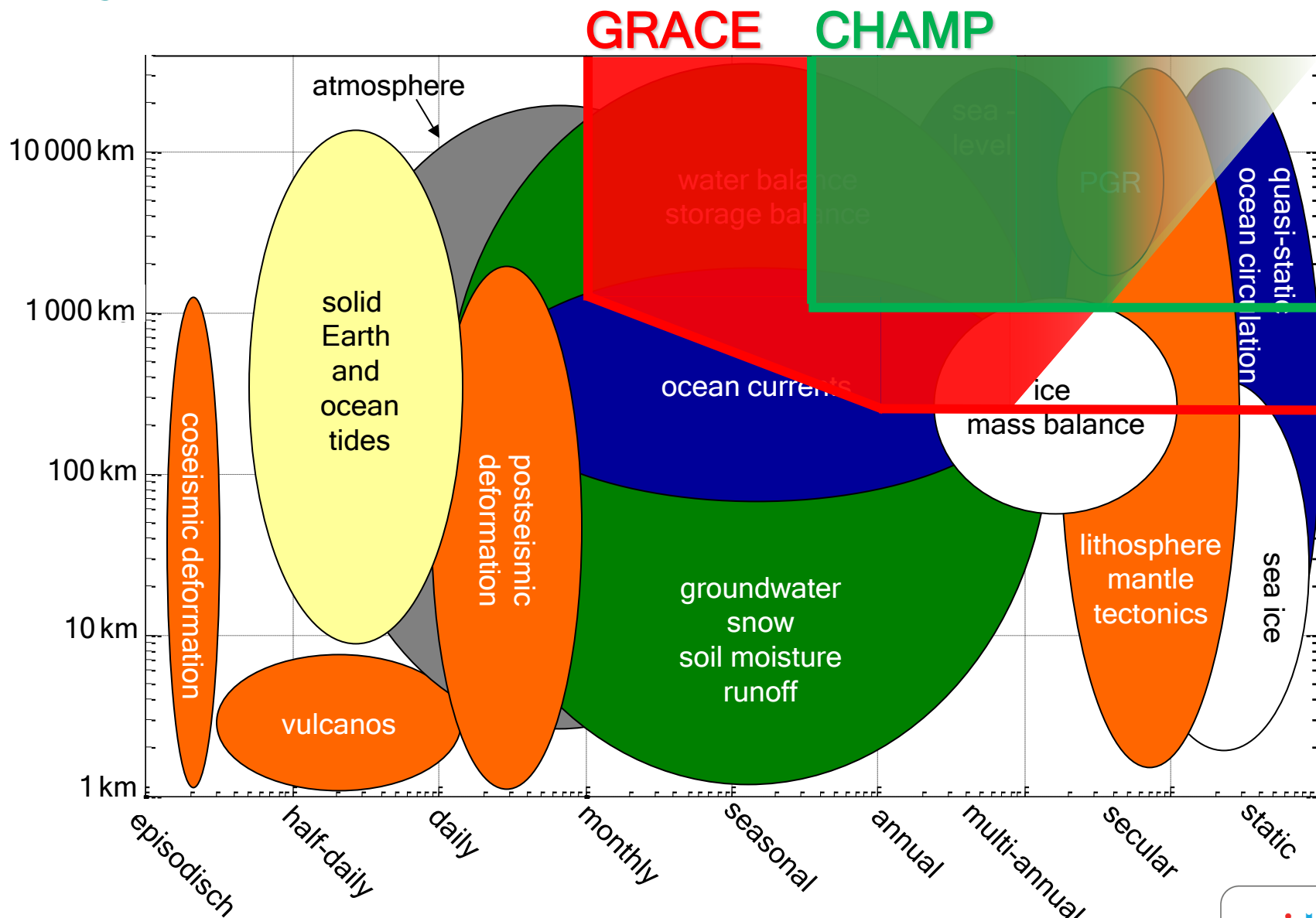
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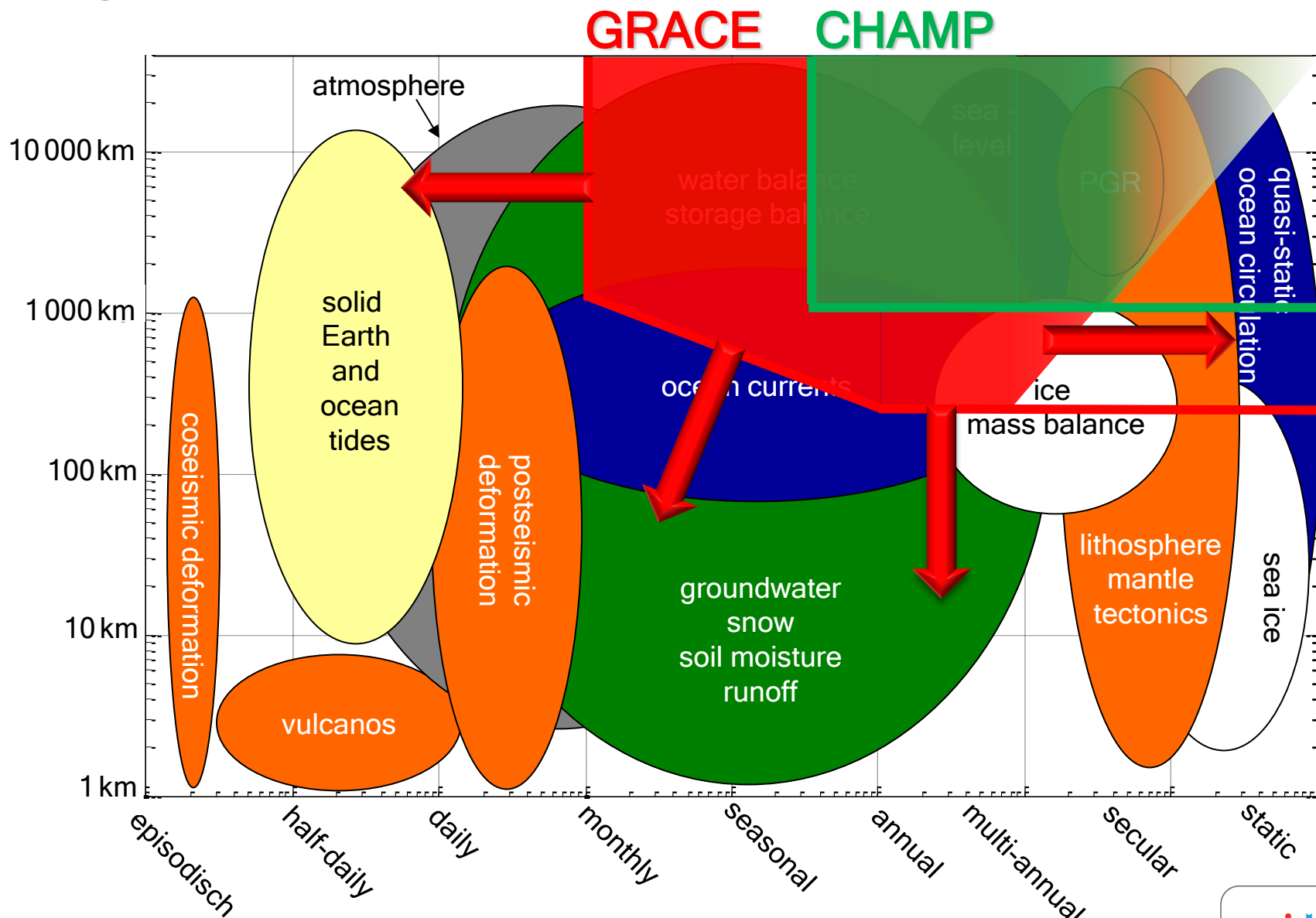
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Beyond GRACE Follow-On



Beyond GRACE Follow-On



Summary

- *The decade of the potential yield an improvement in the gravity field by three orders of magnitude.*
- *Time variable gravity can be observed for the first time with a monthly sampling.*
- *Ongoing strive for higher spatial and temporal resolution (with a likely setback in the coming years).*

A high-angle, blurred photograph of a crowd of people walking on a light-colored, paved surface. The motion blur gives a sense of a busy, crowded environment. The people are dressed in casual to business-casual attire.

Thank you

Matthias Weigelt

Tonie van Dam

Olivier Francis

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